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THESIS

K8515

PARAMETER PLANE ANALYSIS WITH AN
IBM COMPATIBLE MICROCOMPUTER

by

Richard John Kranz III

December 1988

Thesis Advisor: George J. Thaler

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T242018

REPORT DOCUMENTATION PAGE

a. REPORT SECURITY CLASSIFICATION Unclassified		1b RESTRICTIVE MARKINGS										
a. SECURITY CLASSIFICATION AUTHORITY		3. DISTRIBUTION/AVAILABILITY OF REPORT Approved for public release; Distribution is unlimited										
b. DECLASSIFICATION/DOWNGRADING SCHEDULE												
d. PERFORMING ORGANIZATION REPORT NUMBER(S)		5. MONITORING ORGANIZATION REPORT NUMBER(S)										
a. NAME OF PERFORMING ORGANIZATION Naval Postgraduate School	6b OFFICE SYMBOL (If applicable) 62	7a. NAME OF MONITORING ORGANIZATION Naval Postgraduate School										
c. ADDRESS (City, State, and ZIP Code) Monterey, California 93943-5000		7b. ADDRESS (City, State, and ZIP Code) Monterey, California 93943-5000										
a. NAME OF FUNDING/SPONSORING ORGANIZATION	8b OFFICE SYMBOL (If applicable)	9. PROCUREMENT INSTRUMENT IDENTIFICATION NUMBER										
c. ADDRESS (City, State, and ZIP Code)		10. SOURCE OF FUNDING NUMBERS <table border="1" style="width: 100%; border-collapse: collapse;"> <tr> <td style="width: 25%;">PROGRAM ELEMENT NO.</td> <td style="width: 25%;">PROJECT NO.</td> <td style="width: 25%;">TASK NO.</td> <td style="width: 25%;">WORK UNIT ACCESSION NO.</td> </tr> </table>		PROGRAM ELEMENT NO.	PROJECT NO.	TASK NO.	WORK UNIT ACCESSION NO.					
PROGRAM ELEMENT NO.	PROJECT NO.	TASK NO.	WORK UNIT ACCESSION NO.									
1. TITLE (Include Security Classification) PARAMETER PLANE ANALYSIS WITH AN IBM COMPATIBLE MICROCOMPUTER												
2. PERSONAL AUTHOR(S) KRANZ, Richard J. III												
3a. TYPE OF REPORT Master's Thesis	13b TIME COVERED FROM _____ TO _____	14. DATE OF REPORT (Year, Month, Day) 1988 December	15 PAGE COUNT 141									
6. SUPPLEMENTARY NOTATION The views expressed in this thesis are those of the author and do not reflect the official policy or position of the Department of Defense or the U. S Government.												
7. COSATI CODES <table border="1" style="width: 100%; border-collapse: collapse;"> <tr> <th>FIELD</th> <th>GROUP</th> <th>SUB-GROUP</th> </tr> <tr> <td> </td> <td> </td> <td> </td> </tr> <tr> <td> </td> <td> </td> <td> </td> </tr> </table>		FIELD	GROUP	SUB-GROUP							18. SUBJECT TERMS (Continue on reverse if necessary and identify by block number) Parameter Plane, Automatic Feedback Control, Mitrovic's Technique	
FIELD	GROUP	SUB-GROUP										
19. ABSTRACT (Continue on reverse if necessary and identify by block number) A group of lesser used analog control system design techniques, generally termed parameter plane methods, is examined through the use of an IBM compatible microcomputer program developed as part of this thesis. The coefficients of a system's characteristic polynomial are determined by the plant and any added compensators. As these coefficients are varied, so too are the roots of the characteristic equation and therefore the system response in terms of bandwidth, settling time, etc. In the parameter plane method, a designer selects two parameters of a system's compensator(s). The parameters commonly represent such attributes as a compensator gain, pole or zero but can be any linear system function. One or more system characteristics dictating desired system performance, such as relative damping or undamped natural frequency, are computer model inputs. The associated parameter values to achieve the input characteristics are output in graphical and/or tabular form.												
20. DISTRIBUTION/AVAILABILITY OF ABSTRACT <input checked="" type="checkbox"/> UNCLASSIFIED/UNLIMITED <input type="checkbox"/> SAME AS RPT. <input type="checkbox"/> DTIC USERS		21. ABSTRACT SECURITY CLASSIFICATION UNCLASSIFIED										
22a. NAME OF RESPONSIBLE INDIVIDUAL THALER, George J.		22b. TELEPHONE (Include Area Code) 408-646-2134	22c. OFFICE SYMBOL 62Tr									

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Parameter Plane Analysis of Automatic Control
Systems Using an IBM Compatible Microcomputer

by

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MASTER OF SCIENCE IN ELECTRICAL ENGINEERING

from the

NAVAL POSTGRADUATE SCHOOL
December 1988

ABSTRACT

A group of lesser used analog control system design techniques, generally termed parameter plane methods, is examined through the use of an IBM compatible microcomputer program developed as part of this thesis.

The coefficients of a system's characteristic polynomial are determined by the plant and any added compensators. As these coefficients are varied, so too are the roots of the characteristic equation and therefore the system response in terms of bandwidth, settling time, etc.

In the parameter plane method, a designer selects two parameters of a system's compensator(s). The parameters commonly represent such attributes as a compensator gain, pole, or zero but can be any linear system function. One or more system characteristics dictating desired system performance, such as relative damping or undamped natural frequency, are computer model inputs. The associated parameter values to achieve the input characteristics are output in graphical and/or tabular form.

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I. INTRODUCTION

A. BACKGROUND

Over the past decade, a resurgence in interest in analog design techniques has been triggered most notably with the advent of the switched capacitor networks. These networks combine analog and digital technology on one chip. Proven analog design techniques which had been eclipsed by digital design methodology have had new life breathed into them. It is widely recognized that they are still valid tools in the design of modern control systems.

This thesis will examine a group of lesser used analog techniques termed parameter plane methods, parameter space methods or Mitrovic's method. This method enables the user to observe changes in the dynamic behavior (e.g., natural frequency, damping ratio, settling time) of the system when certain parameters, such as poles, zeros or gain, are adjusted.

Through the transformation of the differential equations that describe a linear system into algebraic equations in the s-domain, a characteristic polynomial for that system can be obtained. In a feedback control system, the coefficients of this polynomial are determined by the plant and any added compensators. The roots of the characteristic polynomial theoretically determine the

system response in terms of bandwidth, settling time, steady-state accuracy, overshoot, etc. As the coefficients of the characteristic polynomial are varied, so too are the roots and the associated system response characteristics. Two parameters of the characteristic equation α and β , are varied within user defined ranges to produce a plot with these two parameters representing the abscissa and ordinate. In essence, the characteristic polynomial acts as a mapping function whereby s-plane contours are mapped onto the $\alpha - \beta$ plane. One can plot a family of parameter plane curves for various constant values of ζ , ω_n , $\zeta\omega_n$ and/or σ .* By selecting a desired operating point using these curves, the associated α and β values can be graphically determined. The parameter plane plot provides the user with a visual means of deducing how the dominant roots of the characteristic equation move about in the s-plane as the values of α and β are varied.

*In a controls system, ζ is the relative damping coefficient, ω_n is the undamped natural frequency and σ is the real part of a root of the system's characteristic equation. The product $\zeta\omega_n$ provides an indication of the settling time of a system, where the settling time is commonly equated to $4/\zeta\omega_n$. All four of these parameters can be precisely determined given a specific characteristic equation root value. Chapter 2 discusses these parameters and Figure 2-2 depicts a root on the s-plane.

B. PURPOSE

There currently exists at the Naval Postgraduate School a parameter plane subprogram of a major controls systems program residing on the school's IBM 370 mainframe. While offering excellent graphics resolution coupled with the availability of other analysis tools, such as the root locus method, in the same controls analysis package, it lacks the portability and ready accessibility inherent with personal computer compatible programs. Current microprocessor capabilities justify the development of a parameter plane program for analysis on a personal computer.

The parameter plane routine developed for this thesis incorporates algorithms which were originally proposed by D. Mitrovic [Ref. 1] and expanded upon and made more versatile by D.D. Siljak [Ref. 2] and G.J. Thaler [Refs. 3 and 4]. These basic algorithms were used by R.M. Nutting in the development of his thesis [Ref. 5] which included a parameter plane program supported by a mainframe computer. Over two decades had passed when D.M. Potter, taking advantage of improved computer codes and vastly superior processors and computer architecture, updated Nutting's program as part of his thesis [Ref. 6] by coding in Fortran 77, simplifying user/machine interactions and utilizing the DISSPLA graphics package available on the school's mainframe.

In addition to the portability and versatility gained through the use of microcomputer compatible programs, the parameter plane program developed in conjunction with this thesis improves user friendliness over existing similar programs. Improvements include the incorporation of menu-driven prompts which provide a user with multiple available options on a single screen. This presentation permits rapid selection of desired functions and plots, including the selection of many commonly desired curve groups with one key stroke. It also allows a user to bypass options not needed on a particular analysis. In addition, the existing mainframe parameter plane routine requires an exceedingly long time to generate and plot the user selected constant curves on the $\alpha - \beta$ plane. This problem is exacerbated when mainframe computer usage load is high. The parameter plane routine presented in this thesis generates and displays plots in significantly less time and with much greater flexibility than was previously possible.

II. PARAMETER PLANE DEVELOPMENT

A. HISTORY

A linear system can be formulated as a single ordinary linear differential equation with constant coefficients. Through the application of the Laplace transform, this differential equation is conveyed from the time domain to the frequency or s-domain and consequently can be manipulated using algebraic techniques. The solution to the algebraic problem of synthesizing a control system was published in a paper by Dusan Mitrovic in 1959 [Ref 1].

Mitrovic's method operates in terms of both the frequency and time domains. It is an analysis and design technique of linear feedback control systems which applies graphical methods to algebraic equations. Mitrovic's procedure is based upon conformal mapping from the s-plane to the coefficient ($\alpha - \beta$) plane through the characteristic equation. This methodology transforms an s-plane presentation into the real domain. The real domain in this case is defined by a coefficient plane whose coordinate axes are two parameters (α and β) of the characteristic equation. These parameters appear in the coefficients of the characteristic polynomial.

In the masters theses of H.H. Chon [Ref. 7] and C.H. Hyon [Ref. 8], Mitrovic's method was applied to a variety

of linear feedback control systems thus illustrating the many useful applications of this technique. However, a major limitation of Mitrovic's method exists in that only two coefficients of the characteristic polynomial can be considered as variables. In real world systems, the desired adjustable system parameters, such as system gain and a pole of a compensator, are often located in more than two coefficients of the characteristic polynomial. Straightforward application of Mitrovic's technique could not be accomplished in such cases.

Recognizing this limitation, D.D. Siljak expanded upon Mitrovic's work by introducing Chebyshev functions in the graphical procedure of the method in 1964 [Ref. 2:pp. 451-453]. This addition simplified Mitrovic's procedure and made it more convenient for computer simulation.

B. BASIC ALGEBRAIC RELATIONSHIPS

The characteristic equation of a feedback control system is simply the denominator of the closed loop transfer function of that system. Given a simple unity feedback system as presented in Figure (2-1), the closed loop transfer function is defined as:

$$\frac{C(s)}{R(s)} = \frac{N(s)}{N(s) + D(s)} = \frac{p(s)}{f(s)} \quad (2-1)$$

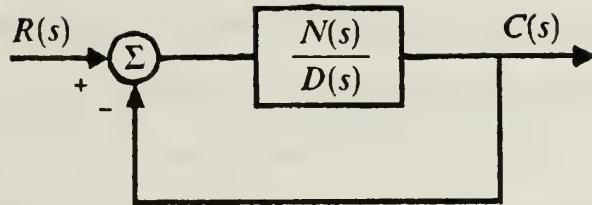


Figure 2-1
Simple Unity Feedback System

$p(s)$ and $f(s)$ are polynomials in the s-domain. The characteristic equation of this system is $f(s)$ and is of the form:

$$f(s) = s^n + a_{n-1}s^{n-1} + a_{n-2}s^{n-2} + \dots + a_2s^2 + a_1s + a_0 \quad (2-2)$$

This form occurs after dividing all terms of the equation by the highest order coefficient (coefficient of s^n).

Mitrovic illustrates the transformation of a characteristic polynomial in the s-domain into one which is a function of ω_n (the undamped natural frequency) and ζ (the relative damping coefficient) by assigning:

$$s = \omega_n e^{j(\frac{\pi}{2} + \theta)} = -\omega_n \sin \theta + j\omega_n \cos \theta = -\omega_n \zeta + j\omega_n \sqrt{1 - \zeta^2} \quad (2-3)$$

where

$$0 \leq \theta \leq \frac{\pi}{2} \quad \text{and} \quad 0 \leq \zeta \leq 1$$

The original lowest order coefficients of the s-domain characteristic equation are then defined as:

$$a_1 = a_2\phi_2(\zeta)\omega_n + a_3\phi_3(\zeta)\omega_n^2 + \dots + a_n\phi_n(\zeta)\omega_n^{n-1} \quad (2-4)$$

$$a_0 = -\omega_n^2[a_2\phi_1(\zeta) + a_3\phi_2(\zeta)\omega_n + \dots + a_n\phi_{n-1}(\zeta)\omega_n^{n-2}] \quad (2-5)$$

Functions $\phi_k(\zeta)$ are fixed values regardless of the degree or coefficient values of the characteristic equation. $\phi_k(\zeta)$ is calculated by:

$$\phi_k(\zeta) = -[2\zeta\phi_{k-1}(\zeta) + \phi_{k-2}(\zeta)] \quad (2-6)$$

with

$$\phi_0(\zeta) = 0 \text{ and } \phi_1(\zeta) = -1$$

A plot can be constructed, with parameters a_0 and a_1 as coordinate axes, by calculating the values of a_0 and a_1 as ζ and ω_n are varied over a user defined range. This method obviously lends itself well to digital computer solution.

Analysis of stability and system compensation are important applications with this technique. Through the selection of particular values for a_0 and a_1 corresponding to desired ζ and/or ω_n values, the transient response of the system can be molded.

The ζ equals zero curve corresponds to the imaginary axis of the s-plane. This is the critical line determining system stability. By examining the ζ equals zero curve on

the parameter plane defined by a_0 and a_1 , values can be determined that yield a stable system.

As previously stated, Siljak introduced Chebyshev functions in the graphical procedure of Mitrovic's method. As did Mitrovic, he expressed s in terms of ζ and ω_n as depicted in Equation (2-3). The relationship of ζ and ω_n in the s -plane is illustrated in Figure 2-2.

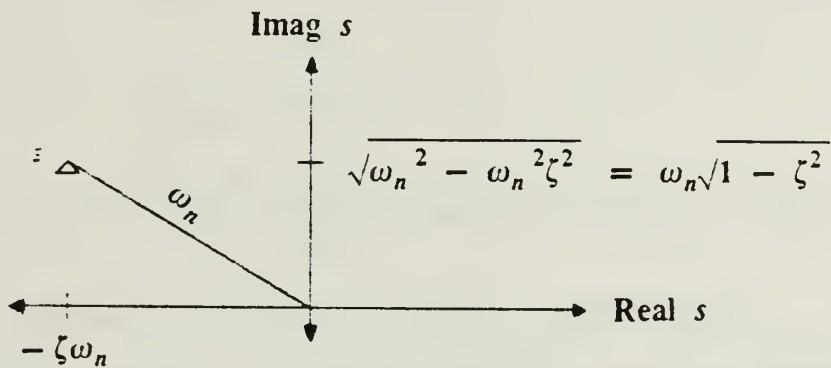


Figure 2-2
S-Plane

$$s = -\omega_n \zeta + j\omega_n \sqrt{1 - \zeta^2}$$

He then applied Chebyshev functions $T_k(\zeta)$ and $U_k(\zeta)$ to transform Equation (2-3) into:

$$s^k = \omega_n^k [T_k(-\zeta) + j\sqrt{1 - \zeta^2} U_k(-\zeta)] \quad (2-7)$$

where

$$T_k(-\zeta) = (-1)^k T_k(\zeta) \quad (2-8)$$

$$U_k(-\zeta) = (-1)^{k+1} U_k(\zeta) \quad (2-9)$$

The argument ζ of the Chebyshev functions is restricted to $0 \leq \zeta \leq 1$ for stable systems.

The functions $T_k(\zeta)$ and $U_k(\zeta)$ can be calculated through application of the recurrence formulas:

$$T_{k+1}(\zeta) - 2\zeta T_k(\zeta) + T_{k-1}(\zeta) = 0 \quad (2-10)$$

$$U_{k+1}(\zeta) - 2\zeta U_k(\zeta) + U_{k-1}(\zeta) = 0 \quad (2-11)$$

where

$$T_0(\zeta) \equiv 1$$

$$T_1(\zeta) \equiv \zeta$$

$$U_0(\zeta) \equiv 0$$

$$U_1(\zeta) \equiv 1$$

Alternately, the Chebyshev function values can be computed using trigonometric functions as follows:

$$T_k(\zeta) = \cos(k \arccos \zeta) \quad (2-12)$$

$$U_k(\zeta) = \frac{\sin(k \arccos \zeta)}{\sin(\arccos \zeta)} \quad (2-13)$$

Siljak then substitutes the value of s derived in Equation (2-7) into the equation for a characteristic polynomial as shown in Equation (2-2). By applying the condition that the summation of the real terms and the imaginary terms must go to zero independently, the characteristic polynomial can be rewritten as two simultaneous equations:

$$\sum_{k=0}^m a_k \omega_n^k T_k(-\zeta) = 0 \quad (2-14)$$

$$\sum_{k=0}^m a_k \omega_n^k U_k(-\zeta) = 0 \quad (2-15)$$

The function $T_k(\zeta)$ may be expressed in terms of $U_k(\zeta)$ as follows:

$$T_k(\zeta) = \zeta U_k(\zeta) - U_{k-1}(\zeta) \quad (2-16)$$

Redefining $T_k(-\zeta)$ and $U_k(-\zeta)$ in terms of Equations (2-8) and (2-9) yields:

$$\sum_{k=0}^m (-1)^k a_k \omega_n^k U_{k-1}(-\zeta) = 0 \quad (2-17)$$

$$\sum_{k=0}^m (-1)^k a_k \omega_n^k U_k(-\zeta) = 0 \quad (2-18)$$

The coefficients of the characteristic polynomial can be divided into α , β and constant terms in this manner:

$$a_k = b_k \alpha + c_k \beta + d_k \quad (2-19)$$

Substituting the preceding equation into Equations (2-17) and (2-18) results in the following simultaneous equations:

$$\alpha B_1(\omega_n, \zeta) + \beta C_1(\omega_n, \zeta) + D_1(\omega_n, \zeta) = 0 \quad (2-20)$$

$$\alpha B_2(\omega_n, \zeta) + \beta C_2(\omega_n, \zeta) + D_2(\omega_n, \zeta) = 0 \quad (2-21)$$

where

$$\begin{aligned} B_1 &= \sum_{k=0}^m (-1)^k b_k \omega_n^k U_{k-1} \\ B_2 &= \sum_{k=0}^m (-1)^k b_k \omega_n^k U_k \\ C_1 &= \sum_{k=0}^m (-1)^k c_k \omega_n^k U_{k-1} \\ C_2 &= \sum_{k=0}^m (-1)^k c_k \omega_n^k U_k \\ D_1 &= \sum_{k=0}^m (-1)^k d_k \omega_n^k U_{k-1} \\ D_2 &= \sum_{k=0}^m (-1)^k d_k \omega_n^k U_k \end{aligned} \quad (2-22)$$

Cramer's rule can be applied to the solution of the two simultaneous equations defined in Equations (2-20) and (2-21):

$$\alpha = \frac{C_1 D_2 - C_2 D_1}{B_1 C_2 - B_2 C_1} \quad (2-23)$$

$$\beta = \frac{B_2 D_1 - B_1 D_2}{B_1 C_2 - B_2 C_1} \quad (2-24)$$

Holding ζ , ω_n or $\zeta\omega_n$ constant and solving the preceding equations while varying the other parameters yields a loci

of points corresponding to the roots of the characteristic equation with constant relative damping, undamped natural frequency or settling time.

However, if adjustments of α and β to achieve a settling time associated with a particular $\zeta\omega_n$ value are of primary concern, Equation (2-3) should be rewritten as:

$$s^k = P_k(\zeta\omega_n, \omega_n^2) + j\omega_n\sqrt{1 - \zeta^2} Q_k(\zeta\omega_n, \omega_n^2) \quad (2-25)$$

The functions P_k and Q_k are related to the Chebyshev functions T_k and U_k as follows:

$$P_k(\zeta\omega_n, \omega_n^2) = \omega_n^{-k} T_k(-\zeta) = (-1)^k \omega_n^{-k} T_k(\zeta) \quad (2-26)$$

$$Q_k(\zeta\omega_n, \omega_n^2) = \omega_n^{-k-1} U_k(-\zeta) = (-1)^{k+1} \omega_n^{-k-1} U_k(\zeta) \quad (2-27)$$

The recurrence formulae associated with P_k and Q_k are:

$$P_{k+1} + 2\zeta\omega_n P_k + \omega_n^2 P_{k-1} = 0 \quad (2-28)$$

$$Q_{k+1} + 2\zeta\omega_n Q_k + \omega_n^2 Q_{k-1} = 0 \quad (2-29)$$

where

$$P_0(\zeta\omega_n, \omega_n^2) \equiv 1$$

$$P_1(\zeta\omega_n, \omega_n^2) \equiv -\zeta\omega_n$$

$$Q_0(\zeta\omega_n, \omega_n^2) \equiv 0$$

$$Q_1(\zeta\omega_n, \omega_n^2) \equiv 1$$

As with T_k and U_k , P_k can be expressed in terms of Q_k :

$$P_k = -\zeta\omega_n Q_k - \omega_n^2 Q_{k-1} \quad (2-30)$$

In the same manner as Equations (2-17) and (2-18) were derived, Siljak produced two simultaneous equations in terms of Q_k :

$$\sum_{k=0}^m a_k Q_{k-1} = 0 \quad (2-31)$$

$$\sum_{k=0}^m a_k Q_k = 0 \quad (2-32)$$

Once again, as in Equation (2-19), a_k is made up of α, β and constant terms. Therefore, the solutions to α and β in this case are identical to Equations (2-23) and (2-24). However, the expressions for B_1 , B_2 , C_1 , C_2 , D_1 and D_2 now become:

$$\begin{aligned} B_1 &= \sum_{k=0}^m b_k Q_{k-1} \\ B_2 &= \sum_{k=0}^m b_k Q_k \\ C_1 &= \sum_{k=0}^m c_k Q_{k-1} \\ C_2 &= \sum_{k=0}^m c_k Q_k \\ D_1 &= \sum_{k=0}^m d_k Q_{k-1} \\ D_2 &= \sum_{k=0}^m d_k Q_k \end{aligned} \quad (2-33)$$

As with functions $\phi_k(\zeta)$, both Chebyshev functions are fixed values, not affected by differences in coefficient values or the degree of the characteristic polynomial. Once again, solution of Mitrovic's method incorporating Chebyshev functions lends itself nicely to digital computer techniques.

III. PARAMETER PLANE PROGRAM DESCRIPTION

A. BACKGROUND

1. Introduction

The parameter plane program is menu driven whenever possible. Many menus have an option to select other menus and these, in turn, may have that same feature. If the program user does not wish to examine particular curves, printer or labeling options, roots, etc., he is not subject to stepping through unwanted menus or responses.

2. Software/Hardware

The programming language used in coding this program is Microsoft FORTRAN77 V4.01. The Plotworks PLOT88 graphics library is used to generate output plots.

All simulations conducted for this thesis were performed on IBM-AT or IBM compatible 80286 machines. Due to the universality of FORTRAN coding, this program could be implemented on any machine capable of being programmed in FORTRAN. The source code for the parameter plane program is listed in Appendix.

A note before running the program. ANSI.SYS should be incorporated in the personal computer's CONFIG.SYS file prior to running the parameter plane program. Through the ANSI.SYS device driver, system calls to clear the screen and position the cursor are enabled. If not, screen

readability suffers although the program is still fully functional. More will be said on this in the ANSI Module section of this chapter.

3. Parameter Plane Program

The parameter plane program itself consists of less than a page of code. Other than assigning default settings to certain variables used throughout the program, its sole function is to serve as a central switchboard to route calls to the eleven major subroutines which make up the parameter plane package.

There is a minor subroutine which is only called when the program is initiated. This subroutine presents an introductory menu entitled 'LOAD/INSERT MENU' (Figure 3-1). It provides options to load a problem from an existing file, input the characteristic polynomial of a system the user wishes to examine, view an example of how to input a characteristic polynomial or quit the program. A flag corresponding to the selected option is set, control is returned to the main program and the selected subroutine is called and executed.

LOAD/INSERT MENU	
OPTION NO.	OPTION
1	LOAD Problem from File
2	INPUT Characteristic Equation
3	EXAMPLE Characteristic Equation Input
9	EXIT to Main Menu

Enter integer number for selection ==>

Figure 3-1
LOAD/INSERT Menu

Upon completion of loading a characteristic polynomial either manually or through a previously created file, a subroutine providing the user with and titled MAIN Menu is called (Figure 3-2). From here, subroutines encompassing all user available options can be selected. These subroutines are grouped into four broad categories.

MAIN MENU	
OPTION NO.	OPTION
1	CURVE Selection Menu
2	PRINTER Selection Menu
3	REVIEW/CHANGE Selections
4	LOAD Problem from File
5	SAVE This Problem
6	INPUT Characteristic Equation
7	PLOT Curves
8	ROOT Finder
9	EXIT Program

Enter integer number for selection ==>

Figure 3-2
MAIN Menu

There are four primary modules associated with the parameter plane routine: a user utilities module, a curve

selection module, a plotting module and a root finding module. In addition, there is a small module consisting of two subroutines; one to clear the screen and the other to position the cursor on the monitor screen. Figure 3-3 is a schematic illustrating the organization and interrelationships of the modules and associated subroutines of the parameter plane package.

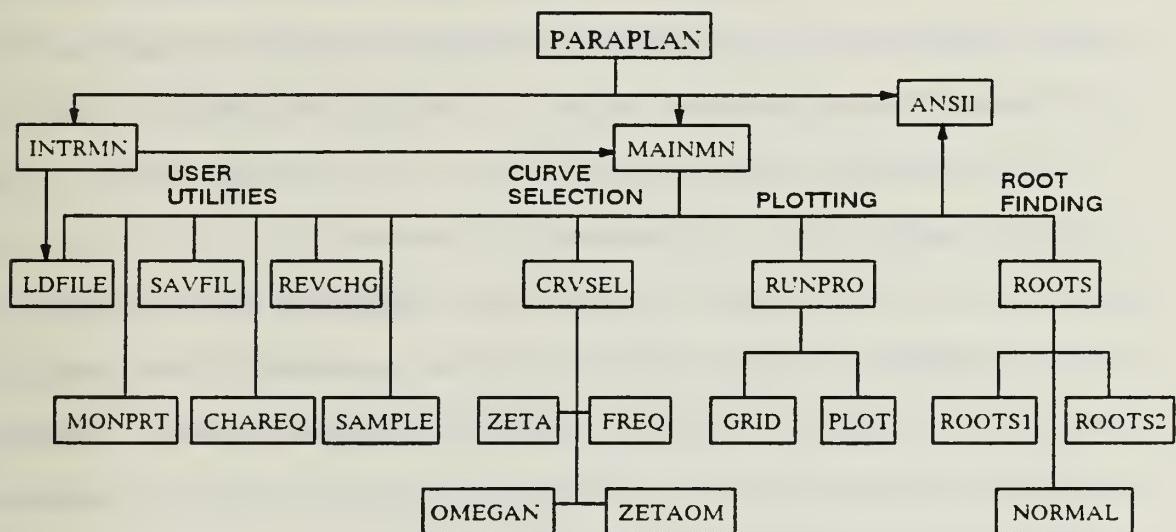


Figure 3-3
Parameter Plane Schematic

B. USER UTILITIES MODULE

1. Overview

The user utilities module contains six subroutines which provide primary call routing procedures, data manipulation and review and output setup. In addition, a sample problem subroutine is incorporated within this module.

2. Subroutine CHAREQ

The provision for manually inputting a characteristic polynomial is provided through Subroutine CHAREQ. The initial prompt displayed upon calling this subroutine requests entry of the order of the characteristic equation. A ninth-order polynomial is the maximum size limitation.

Chapter II goes into great detail explaining the development of the parameter plane method. Equation 2-19 defines the algebraic form of each coefficient of the characteristic polynomial. One can see that each coefficient term is composed of three parts, in this case defined as an alpha, a beta and a constant part. Alpha and beta are the two user defined parameters which the designer wishes to set to obtain certain desired system response characteristics. A coefficient containing only a constant part is not affected when system characteristics such as relative damping or undamped natural frequency are altered. These alterations will of course change the values for alpha and/or beta however. Subsection 6 in this section titled Subroutine SAMPLE provides a simple example on the mechanics of assigning values to the constant, alpha and beta coefficient terms. Chapter IV illustrates solving more complex problems with the parameter plane method.

Following input of system order, requests are made to separately enter the three parts of each characteristic

polynomial coefficient. Constant coefficient terms are entered first. Input is requested from highest order term to lowest. For example, in the case of a third order polynomial, the first prompt would be 'CONSTANT Coefficient of S ** 3 = ' with the cursor positioned just after the equals sign, awaiting user input. In many instances, a polynomial will not contain constant terms for certain coefficients. In these cases, the user must enter a zero for the applicable term(s). When insertion of constant coefficients is complete, they are echoed back and an offer to change incorrectly entered values is provided.

After satisfactory entry of the constant coefficients, the user receives a prompt to enter the alpha coefficient values of the characteristic equation. Once again, these terms apply to the first of two user selected system parameters corresponding to a system or compensator gain, pole, etc. which the user desires to fix in order to achieve a particular set of system characteristics. Chapters I and II discuss the background and development of this method while Chapter IV contains a number of problems which illustrate its application. The same procedures used to enter and verify constant coefficients are used in the alpha value inputs. The user is then prompted to enter the coefficients for the second of two parameters, the beta terms.

When entry of all constant, alpha and beta coefficients is complete, a prompt is made for input of the minimum and maximum undamped natural frequency values over which to calculate all requested relative damping coefficients. Subsection 6 provides an example on determining these values in discussing Subroutine SAMPLE.

A final function of Subroutine CHAREQ, in conjunction with the root finding module, allows one to enter specific values for alpha and beta and then calculate the roots of the existing characteristic equation.

3. Subroutine LDFILE

Subroutine LDFILE permits program input of a preexisting data file. The user is queried as to file name (not to exceed eight characters) and file extension (three characters or less). The code checks for existence of the file within the working subdirectory. If it does not exist, a message is returned stating such and offering the option of entering another file name or returning to the MAIN Menu. Entry of file extension is optional. In fact, a file can be labeled with as little as one character or number.

The data file contains graphics output options (to the monitor or a particular printer type), minimum and maximum frequencies over which to span constant damping coefficient selections, the order of the characteristic polynomial and associated coefficient values. When loaded, all parameter values are displayed on the screen for

verification. It is most easily created using MAIN Menu option 5, 'Save this problem', after an analysis has been run. This option calls Subroutine SAVFIL to be discussed next. A data file could be created using a text editor and aligning the previously stated parameter values in the format identified by the Subroutine LDFILE source code listed in Appendix A. Of course the first method is quicker and less subject to errors.

4. Subroutine SAVFIL

After entering in Subroutine CHAREQ the previously discussed parameters which define a system and the particular range of frequencies of interest, it would be convenient and time efficient to save the system definitive numbers, if one is to look at that same system in the future. Subroutine SAVFIL provides this service. As with Subroutine LDFILE, a prompt is displayed requesting input of file name and file extension. In addition, a check is made to determine if the entered file name plus optional extension already exists. If it does, the option is provided to overwrite the existing file or enter a new file name and extension. The current parameters as outlined in the Subroutine LDFILE subsection are then written to the indicated file. All parameters are also echoed to the screen as a final check for accuracy.

Even high order polynomials require only 300 to 400 bytes of memory, therefore storage of multiple systems

will have little impact on disk space used. Approximately 10,000 high order systems could be stored on a double sided, double density diskette.

5. Subroutine REVCHG

Occasionally, a need arises to review the system coefficient values and frequency range under consideration. This can be done by loading or saving a file or accessing Subroutine FREQ in the Curve Selection Module. In most cases, this procedure can be accomplished more quickly by selecting option 3, 'REVIEW/CHANGE Selection', in the MAIN Menu. This selection calls Subroutine REVCHG. As indicated by the option title, changes to system parameters can be made directly from this subroutine.

6. Subroutine SAMPLE

Subroutine SAMPLE provides a quick tutorial on the derivation and entry of a system's characteristic polynomial. As an example, a universal third order system is presented.

A universal third order system is represented by the characteristic equation $s^3 + As^2 + Bs + 1 = 0$. A and B are the variables defining the two system/compensator parameters to be determined so as to achieve desired system response. This characteristic equation is obtained with a $1/s^3$ plant incorporating both acceleration (s^2) and velocity (s) feedback. A and B (the alpha and beta terms

identified in Equation 2-19) are the respective gains for the two compensators.

To load this characteristic polynomial into the parameter plane model, one would first select option 2 in the introductory LOAD/INSET Menu or option 6 in the MAIN Menu. Each of these option titles is 'INPUT Characteristic Equation'.

A simple examination of the characteristic polynomial shows that the s^2 and s terms have no constant coefficients while the s^3 and constant (1) terms have no alpha (A) or beta (B) terms. Therefore, the response to 'Enter the CONSTANT Coefficient Values of the Characteristic Equation' would be:

```
'CONSTANT Coefficient of s**3 =' 1
'CONSTANT Coefficient of s**2 =' 0
'CONSTANT Coefficient of s**1 =' 0
'CONSTANT Coefficient of s**0 =' 1
```

The response to the alpha and beta coefficient request is:

```
'ALPHA Coefficient of s**3 =' 0
'ALPHA Coefficient of s**2 =' 1
'ALPHA Coefficient of s**1 =' 0
'ALPHA Coefficient of s**0 =' 0

'BETA Coefficient of s**3 =' 0
'BETA Coefficient of s**2 =' 0
'BETA Coefficient of s**1 =' 1
'BETA Coefficient of s**0 =' 0
```

Entry of minimum and maximum values of undamped natural frequency would be dictated by the desired system response characteristics. For example, a settling time (T_s)

under 2 seconds is required. System settling time is approximated by four divided by the product of relative damping coefficient (zeta) and natural undamped frequency (ω_n). Since zeta is restricted to values between zero and one, ω_n ranges can be calculated (using minimum value of .1 for zeta). The result is that ω_n can vary between 2 and 20, therefore enter these values as minimum and maximum frequency.

7. Subroutine MONPRT

The largest of the subroutines within the User Utilities Module is Subroutine MONPRT. A number of smaller subroutines are associated with it. Subroutine MONPRT allows selection of the graphics output device, be it the monitor or a wide variety of printers. Graphics output defaults to the monitor when the program is first executed. Graphics output can always be dumped from the screen to a printer, but there may be times when direct output to a printer is desired. All NPS printers are included in the printer output options. In addition, one option permits the user to directly enter the values for IOPORT and MODEL, as outlined in the PLOT88 Manual [Ref. 10].

The first menu displayed when Subroutine MONPRT is called is the PRINTER/OUTPUT Menu (Figure 3-4). Selection of a printer in this menu automatically directs graphics output to the most commonly associated output port, either parallel or serial, for that particular device. However,

usually there are multiple parallel or serial ports to which a printer can be attached. The default printer output setting may not direct plots to the appropriate port. To provide maximum output flexibility, the PRINTER/OUTPUT Menu allows selection of a specific output port through access to another menu.

PRINTER/OUTPUT MENU	
PRINTER NO.	PRINTER
1	Epson FX-80, All
2	Epson FX-100, All
3	Epson MX-100, All
4	Epson RX-80, All
5	Epson MX-80 & IBM Printer
6	HP 7470A Graphics Plotter
7	HP 7475A Graphics Plotter
8	HP 758xB Series Plotters
9	HP 2686A Laser Jet
10	Graphics Monitor (default)
11	HARDWARE Interface Menu
12	Input PLOT88 Values for IOPORT and MODEL
99	EXIT to Main Menu

Enter integer number for selection ==>

Figure 3-4
PRINTER/OUTPUT Menu

The output port selection option is called the HARDWARE Interface Menu (Figure 3-5). This menu is part of a subordinate MONPRT subroutine titled PORT. The options allow selection of one of three parallel ports (LPT1 - LPT3) or either of two serial ports (COM1 - COM2).

HARDWARE INTERFACE MENU	
SELECT NO.	PORT
1	LPT1 Printer Port
2	LPT2 Printer Port
3	LPT3 Printer Port
4	COM1 Serial Port
5	COM2 Serial Port
99	EXIT to Main Menu

Enter integer number for selection ==>

Figure 3-5
HARDWARE INTERFACE Menu

If a serial port is manually selected in the HARDWARE INTERFACE Menu, an associated data transfer (baud) rate must also be assigned. Immediately after selection of serial port options 4 or 5, the BAUD (data transfer) RATE Menu is displayed (Figure 3-6). Transfer of graphics data over a single line is usually time consuming, therefore the highest printer capable transfer rate available (9600 baud) is normally the best selection. A slower transfer rate would only be indicated if improper graphics output is generated.

BAUD (data transfer) RATE MENU	
SELECT NO.	BAUD RATE
1	300
2	1200
3	4800
4	9600

Enter integer number for selection ==>

Figure 3-6
BAUD (data transfer) RATE Menu

Bit by bit transfer of data can also have a check sum (parity) associated with it to provide an internal check of correct data transfer. Following selection of a data transfer rate, the PARITY Menu is displayed. The user has the option of choosing odd, even or no parity.

PARITY MENU	
SELECT NO.	PARITY
1	NO Parity
2	EVEN Parity
3	ODD Parity

Enter integer number for selection ==>

Figure 3-7
PARITY Menu

The PLOT88 Software Library Reference Manual [Ref. 10] contains a number of tables which provide common output settings for many more printers than can be selected in the PRINTER/OUTPUT Menu.

C. CURVE SELECTION MODULE

1. Overview

The Curve Selection Module contains only one subroutine. However, Subroutine CRVSEL is the single largest subroutine in the entire program and contains all of the coding that makes this program a parameter plane analysis tool. Attempts were made to subdivide this large subroutine into many function specific smaller ones. Apparent Fortran compiler limitations due to the overall size of the program frustrated this effort.

Numerous menus in Subroutine CRVSEL permit the user to rapidly select a variety of data display and file options as well as commonly desired constant parameter curves such as the zeta equals zero curve, defining the system stability limit. These menus also allow one to easily determine the curve selection process level and provide the ability to backtrack if necessary.

Three constant parameter choices are offered for solution of alpha and beta values associated with a particular root position and subsequent plotting on the alpha/beta plane. The first of these choices is the constant zeta contour. Zeta is the variable normally assigned to the relative damping coefficient. It is represented on the s-plane as a radial vector extending outward from the origin and is directly related to system steady state overshoot. The zeta equals zero curve is the

imaginary axis of the s-plane while the zeta equals one curve falls on the real axis. The second contour available for plotting is the constant ω_n curve representing system undamped natural frequency. Its s-plane representation is a curve of constant magnitude about the origin. The intersection of these two contours exactly defines a system root location. The final curve is the product of the first two contours and indicates the transient response of the system. This curve plots as a straight line on the s-plane parallel to the imaginary axis. System settling time is usually defined as four divided by the zeta- ω_n product. The interrelationship of these terms with the s-plane is depicted in Figure 2-2.

2. Subroutine CRVSEL

Subroutine CRVSEL is called from the main program through selection of option one in the MAIN Menu, labeled CURVE Selection Menu. Upon selection of this option, the CURVE DATA POINT DISPLAY Menu appears on the screen (Figure 3-8). Option selection from this menu determines if the user is provided with a screen display of every tenth alpha/beta pair and/or all alpha/beta solutions are routed to a data file for future reference. Another available option provides neither a screen display of alpha/beta pairs nor a dump of these data points to file. Selection of this option speeds the curve construction process slightly by avoiding I/O and may be the preferred option if only a

quick graphical overview is desired. The CURVE DATA POINT DISPLAY Menu also provides the option of computing system closed loop root values associated with each alpha/beta pair. These roots can be displayed on the screen and/or written to a file.

CURVE DATA POINT DISPLAY MENU	
OPTION NO.	OUTPUT SELECTION
1	NO output DISPLAY or save to FILE
2	DISPLAY every 10th alpha/beta value
3	DISPLAY alpha/beta values and roots
4	DISPLAY & FILE alpha/betas and roots
5	FILE all alpha/beta values
6	FILE all alpha/beta values and roots

Enter integer number for selection ==>

Figure 3-8
CURVE DATA POINT DISPLAY Menu

When options 4,5 or 6 are made in the CURVE DATA POINT DISPLAY Menu, indicating that calculated data is to be filed, the user is queried as to name and extension of the data file to be opened. A check is made to determine if the entered data file name and extension already exists. If it does, the user is given a choice to overwrite that file with newly generated data or open a new file under another file name.

When the data display and storage procedures just discussed are completed, the primary menu of this subroutine is displayed. It is called the CURVE SELECTION Menu (Figure 3-9) for obvious reasons. In addition to

options allowing selection of any one of the three constant parameter curves previously outlined, options to change the frequency range over which constant zeta contours are calculated, plot the selected curves or return to the MAIN Menu are offered.

CURVE SELECTION MENU	
OPTION NO.	CURVE SELECTION
1	Constant ZETA Curves
2	Constant OMEGA Curves
3	Constant ZETA*OMEGA Curves
4	Change Frequency Range
5	PLOT Selected Curves
9	EXIT to Main Menu

Enter integer number for selection ==>

Figure 3-9
CURVE SELECTION Menu

Each of the three curve options permits the selection and plotting of up to ten constant contours. In most instances, a designer is interested in viewing the stability limits of a system, as represented by the zeta equals zero curve. Due to this zeta curve attribute and the fact that for a stable system, zeta is restricted to the range zero to one, a CONSTANT ZETA Menu (Figure 3-10) is provided. The user is given the option of entering particular constant zeta curve values or selecting with a single key stroke the zeta equals zero curve or two other options which equally subdivide the range zero to one into three or five parts. Following identification of constant

zeta curves, the program returns to the CURVE SELECTION Menu to allow selection of other constant curves or plot the current selections.

CONSTANT ZETA MENU	
OPTION NO.	ZETA CURVE SELECTION
1	Select particular constant ZETA curves
2	ZETA = 0 curve
3	ZETA = 0,0.5 and 1.0 curves
4	ZETA = 0,0.25,0.5,0.75,1.0 curves
9	EXIT to Curve Selection Menu

Enter integer number for selection ==>

Figure 3-10
CONSTANT ZETA Menu

Each constant curve is calculated using 100 data points. This value was selected as a compromise between speed of curve generation and precision of plot. A possible update to this program would permit a user entered data point number. This would enable a designer to more closely tailor the parameter plane plots to his or her needs.

Successive data points are linearly incremented in the case of constant ω_n and zeta- ω_n curves. In the generation of successive constant zeta points, a logarithmic increment is used due to the large possible variation between minimum and maximum ω_n values. (In calculating alpha/beta pairs associated with zeta curves, ω_n is varied between minimum and maximum while zeta is held constant).

High order systems often exhibit large variations between successive alpha/beta points. Unfortunately, the PLOT88 graphics package occasionally fails when these variations are extreme (i.e., in excess of five orders of magnitude). To prevent inadvertently halting program execution, two checks are made. The first prevents calculation of an alpha or beta value when the denominator of the defining equation is less than 1.e-12. The second compares successive alpha/beta points for a difference exceeding 1.e5. If either situation occurs, a warning is sent to the monitor and, if applicable, to a data file. The offending alpha/beta pair is then assigned the value of the previously calculated point.

A final procedure available in Subroutine CRVSEL is the selection of minimum and maximum frequencies over which constant zeta curves are calculated. Should this option be exercised after selection of constant zeta curves, the program automatically recalculates the associated alpha/beta points.

D. PLOTTING MODULE

1. Overview

The Plotting Module consists of three subroutines. The primary function of this module is to call PLOT88 Graphics Library Routines which generate the constant curve plots on the alpha-beta plane. The alpha/beta arrays are

passed to this module via a common block. This method was adopted when attempts to pass large arrays as arguments of subroutines resulted in stack overflow errors.

As discussed early in this chapter, the latest released Fortran version was used in compiling and linking this program. Microsoft FORTRAN77 V4.01 contains an optimizing compiler that does not directly translate the source code into an object file but instead alters the code to achieve various user defined objectives. Two common optimizations are increased speed and reduced code size. The Plotting Module holds the distinction as the only module that could not take advantage of this optimization. One or more calls to PLOT88 Routines were distorted to the point that program execution was halted unpredictably. Therefore, the optimization functions of the Fortran compiler were bypassed.

2. Subroutine RUNPRO

Subroutine RUNPRO makes up the bulk of this module. When first called, the PLOTTING Menu (Figure 3-11) is displayed. This menu provides the user with a number of plot presentation and labeling options.

PLOTTING MENU	
OPTION NO.	OPTION
1	TITLE output graph and PLOT data
2	PLOT data (no title)
3	SIZE output graph
4	SYMBOL to be plotted at each data point
9	EXIT to Main Menu

Enter integer number for selection ==>

Figure 3-11
PLOTTING Menu

Option 1 permits entry of a title up to 30 characters in length. A routine computes the length of the entered title then centers it at the top of each graph. The third option permits adjustment of plot size to both the screen and the printer. This option was utilized to scale plot outputs for inclusion in this thesis. Another option allows the user to select a particular symbol to be applied to the plot at each data point. Figure 3-12 illustrates some of the symbol choices available.

Type in an INTEGER number from 0 through 13 to place a symbol at each calculated data point. There are 100 data points for each curve. Examples of symbols with associated numbers:

2	Triangle
3	+
4	X
8	Z
9	Y
11	*
13	Vertical Line

Enter INTEGER number (0 - 13) ==>

Figure 3-12
Symbol Selection Display

A final option permits immediate plotting of data arrays without enhancing the graphical presentation. As with most of the menus, the ability to return to the calling routine, in this case the MAIN Menu, is also available.

Once again, three sets of system parameter curves can be plotted; constant zeta, constant ω_n and constant zeta- ω_n . Each set can contain up to ten separate contours. The program sequentially checks for the existence of any curves in each of the three categories. In addition to alpha/beta values, total number of curves and data points within each category are passed to Subroutine RUNPRO from Subroutine CRVSEL. When one or more curves are detected in a particular category, Subroutine PLTCRV is called to actually compute each curve. Requested curves in all categories are first calculated before the first plot is displayed. Sequencing to succeeding plots is accomplished by depressing the Enter key. All zeta contours are drawn as a series of straight line segments one tenth of an inch long. This procedure gives the appearance of a smooth, continuous contour. ω_n and zeta- ω_n contours are plotted similarly, but with dashed lines made up of different segment lengths.

If both zeta and ω_n curves are present, the last plot consists of both sets of curves. The minimum alpha and beta values and axes increments from the zeta

plot are used to scale this graph. If any ω_n constant contour selection frequencies fall outside the minimum to maximum frequency range designated for constructing the constant zeta curves, these curves may not be displayed within the plotting box. The user can still view the offending contour lines by exiting then reentering the plotting routine and selecting the plot size reduction option in the PLOTTING Menu.

After viewing the requested plots, the user is given the option of focusing on a particular area of the plot. This is accomplished through the EXPAND PLOT Menu (Figure 3-13).

EXPAND PLOT MENU	
OPTION NO.	EXPANSION SELECTION
1	Expand area defined by axes values
2	Expand around a selected point
9	EXIT plotting routine

Enter integer number for selection ==>

Figure 3-13
EXPAND PLOT Menu

A choice is offered to expand a specified area defined by minimum and maximum alpha and beta axes values or expand the plot around a selected point relative to absolute alpha/beta axis positions (e.g., expanding about the center of the plot would be accomplished by entering a value of 3.5 for alpha and 2.5 for beta). The second option

provides the user with a quick look at a particular point however the axes are usually lost with any significant expansion. The first option rescales and displays the alpha and beta axes, therefore it is normally the preferred expansion method.

A few remarks on the mechanics of producing hard copy plots, as they apply to Naval Postgraduate School specific hardware, are in order. Graphics output to a device other than a monitor requires an extended period of time as the data file is loaded into the printer buffer and formatted for hardcopy output. In addition, the user is unable to view the plot when the program has been configured for a non-monitor output device. To avoid these inconveniences, the 'Print Screen' key can be depressed while a desired plot is displayed on the monitor. Printer output is then available in less than a minute. The Laser Jet Printer located in the Controls Lab must be configured as an Epson Printer for the 'Print Screen' function to operate correctly.

3. Subroutine GRID

Subroutine GRID is a short, simple routine called before each plot. It first defines the plot physical origin in relation to the output device. This is usually the monitor screen although it would be a printer page if so defined in Subroutine MONPRT. The origin is presently set at eight tenths of an inch above and to the right of the

output device lower left corner. It cannot be modified by the user.

A box of unmodified dimensions 7" x 5" is drawn from the physical origin, defining the plotting area. In addition, a dashed line grid is inserted at integer intervals of the vertical and horizontal axes. The box, grid lines and contour plots are all size modified (both screen and printer output) through the sizing option of the PLOTTING Menu.

4. Subroutine PLTCRV

This subroutine accepts alpha/beta data arrays and graph title passed by subroutine argument. Common block inputs to size the output plot and place a user identified symbol at each data point are also resident.

An initial call is made to a PLOT88 subroutine specifying axis annotation characteristics such as tic mark placement and axis title height. Next, axes scaling intervals are determined based on alpha and beta value ranges and a respective seven and five unit division of the axes. Additionally, the minimum alpha and beta data point values are identified at this time. The x and y axes minimum and major increment values are displayed on the screen with a message indicating that curve construction is in progress. Meanwhile, a PLOT88 subroutine is called which accepts the 100 data point pairs associated with each constant curve and creates a smoothed contour using the

scaling data previously calculated. Data point symbols are also inserted on each curve if selected by the user in Subroutine RUNPRO. When all contours have been created for a particular parameter (e.g., relative damping coefficient - zeta), control is passed back to Subroutine RUNPRO.

E. ROOT FINDING MODULE

1. Overview

The Root Finding Module is unique among the three major modules of the parameter plane program in that it has no menus associated with it. It is called predominantly from the CRVSEL subroutine of the Main Module when a 'y' response is entered to the question 'Do you want to view the roots of the polynomial?' This question is presented to the user each time calculations for a set of constant curves is requested.

The other option of entering the Root Finding Module is offered in the MAIN Menu as Root Finder. Should the user make this selection, a flag is set, Subroutine ROOTS is called and subsequently the subroutine for inputting a characteristic equation is activated. A choice is given to enter a characteristic equation or find the roots of the current characteristic equation. If the user wishes to enter a new or initial characteristic polynomial, the standard characteristic equation entry procedure is carried out. If not, this portion of Subroutine CHAREQ is

skipped over. In either case, entry of a characteristic equation via the root finding module requires that a user enter specific values for alpha and beta. All associated coefficients of these two variables are multiplied by the respective alpha or beta entries. Subroutine CHAREQ then returns the program to the root finding module for calculation of the input polynomial with specified alpha and beta values. In this manner, one can select particular alpha and beta values and compute all roots of the polynomial with those values.

2. Subroutine ROOTS

ROOTS is the highest level subroutine of the root finding module. Terms defining the order and coefficient values of a polynomial are passed to ROOTS as parameters of the subroutine. Additional parameters passed include the particular alpha and beta values to be used in calculating the coefficients of the polynomial. Another parameter is the flag differentiating between calculation of roots associated with constant curves or the calculation of root values for specific alpha/beta user inputs. A call is made to Subroutine CHAREQ if this flag indicates that the roots of a polynomial associated with a user inputted set of alpha and beta values are to be calculated.

Once the characteristic polynomial is fixed, Subroutine NORMAL is called. This subroutine normalizes the polynomial to ensure that the coefficient of the highest

order term is unity. Finally, Subroutine ROOTS2, which contains the root calculation procedures, is called.

3. Subroutine NORMAL

NORMAL is a subroutine that normalizes the characteristic polynomial. It is also the subroutine which multiplies the alpha and beta coefficient terms by the alpha and beta values passed via subroutine parameters from ROOTS. These two products represent a portion of the coefficient of a particular order term associated with the alpha and beta parameters. They are added to the constant coefficient of that same order term to form the total coefficient of that term. A do loop provides the means for combining the constant, alpha and beta coefficient values into a single coefficient for each term of the polynomial.

When the roots of a polynomial are calculated based upon user input of specific alpha and beta values, Subroutine NORMAL provides another function. In addition to showing the user the roots of the polynomial, the routine also outputs the coefficient values of the polynomial based upon the specific alpha/beta inputs.

4. Subroutine ROOTS1

ROOTS1 is a short subroutine that models the quadratic equation. It calculates the roots of a second order polynomial. This subroutine is called only from the ROOTS2 subroutine after the initial polynomial has been reduced to one of second order.

5. Subroutine ROOTS2

Subroutine ROOTS2 is the heart of the root finding module. The algorithm used in this subroutine iteratively searches for a quadratic factor of the input polynomial. When this factor is found, the original polynomial is reduced by an order of two. This process is repeated until the remainder is a first or second order polynomial. Each time a quadratic factor is found, Subroutine ROOTS1 is called to calculate the roots.

There are two terms in the algorithm that affect both the speed of computation and the accuracy of the solution. The first, labeled EPSILON, sets an acceptable accuracy level for the computed roots. The numerical procedure applies ever decreasing correction factors to the constant and first order terms of the quadratic factor, it is calculating. When the sum of these correction factors is less than an EPSILON value of .00005, the refinement is halted and the roots of the quadratic factor are solved through a call to the ROOTS1 subroutine. In the vast majority of cases, the quadratic factor is determined after relatively few iterations. However, there are cases, especially when the characteristic polynomial contains multiple identical real roots, when the sum of the correction factors is not reduced below EPSILON even after 1000 iterations. If this situation occurs during computation and the routine determines that more than 500

iterations have taken place in determining a single quadratic factor, the procedure is halted and control returned to the calling routine. Should this happen during the computation of roots for multiple alpha/beta values, the alpha and beta values will still be displayed without the associated roots and an attempt to determine roots for the succeeding discrete alpha/beta pair will commence.

The methodology of continually reducing a polynomial by a quadratic factor until all roots are determined is known as Bairstow's method. R.L. Wood incorporated this method in his thesis when he coded a routine which included control systems design through root locus techniques [Ref. 9:pp. 42-43].

F. ANSI MODULE

The ANSI Module contains two subroutines. Subroutine CLR clears the monitor screen. It is used primarily as a precursor to displaying a menu or positioning queries or informational text. Subroutine PSIT positions the cursor immediately after a request for response. This subroutine serves not only to give a pleasing screen display but also provide the user with an immediate reference as to where he is in the program and if an input is required of the user. Both routines can be found in the PLOT88 Reference Manual [Ref. 10:pp. 85-86].

The two subroutines which comprise the ANSI Module make use of ANSI escape sequences. These sequences are a series of characters that can be used to define functions to MS-DOS. In addition to clearing the screen and positioning, moving and saving the cursor's position, ANSI escape sequences can control screen graphics and reassign key definitions.

In order to utilize the escape sequences, the microprocessor must first be able to interpret the commands. It does this through a systems file entitled ANSI.SYS. ANSI.SYS must be defined as a device in the CONFIG.SYS file to enable proper interpretation of ANSI escape sequences (e.g., device=\bin\ansi.sys where \bin\ is the path to ansi.sys). If ANSI.SYS is not resident in the CONFIG.SYS file, the parameter plane program will not clear the screen or position the cursor when so directed. Instead, the indicated escape code sequence will be printed on the monitor whenever a call is made to CLR or PSIT. Although program readability is degraded, parameter plane will still function correctly.

IV. COMPUTER AIDED PARAMETER PLANE ANALYSIS

A. OVERVIEW

An algebraic solution of feedback compensated control systems is usually performed by selecting particular zeta and omega values that provide desired system response characteristics. A pair of complex conjugate roots are thus placed at specific s-plane locations that will provide the designed for response, if these roots are dominant. A check must therefore be made to satisfy the dominance question. If the positioned roots are not dominant, the design scheme must be altered.

Design procedures which select values of zeta and omega to position a pair of complex roots in a position of dominance assume that the contributions of all additional roots can be neglected. Although this is certainly not always the case, applying this simplification permits modeling of complex systems with second order polynomials. As such, the following system response parameter equations can be utilized to derive zeta and omega values which produce desired system behavior:

Maximum Overshoot (step input)

$$M_{pt} = \frac{-\pi\xi}{1 + e^{\sqrt{1-\xi^2}}} \quad (4-1)$$

Settling Time (4 time constants)

$$T_s = \frac{4}{\zeta \omega_n} \quad (4-2)$$

Time of Maximum Overshoot

$$t_p = \frac{\pi}{\omega_n \sqrt{1 - \zeta^2}} \quad (4-3)$$

Bandwidth (response magnitude > .707*input)

$$\omega_b = \omega_n \sqrt{1 - 2\zeta^2 + \sqrt{2 - 4\zeta^2 + 4\zeta^4}} \quad (4-4)$$

Resonance Peak

$$\omega_r = \omega_n \sqrt{1 - 2\zeta^2} \quad (4-5)$$

Transient Oscillating Frequency

$$\omega_t = \omega_n \sqrt{1 - \zeta^2} \quad (4-6)$$

Phase Margin

$$\Phi_m = \tan^{-1} \frac{2\zeta}{\sqrt{-2\zeta^2 + \sqrt{4\zeta^4 + 1}}} \quad (4-7)$$

A graphical solution using the parameter plane technique, with reference to the resident root finding module, provides a designer with a rapid means of determining parameter values satisfying design requirements while ensuring both stability and root dominance. When a family of curves is computed and displayed, the flexibility

of choosing a number of parameter value pairs which may force design compliance is offered.

B. PROBLEM SOLUTIONS

1. Example 4-1

Figure 4-1 illustrates an ideal instrument servo which is to be damped by velocity feedback and a cascaded gain amplifier. The common single parameter root locus method could easily be employed in the solution of this problem by deleting the gain amplifier. However, this stage provides the designer with increased flexibility and illustrates the ease of parameter plane solution in low order systems, despite an additional parameter.

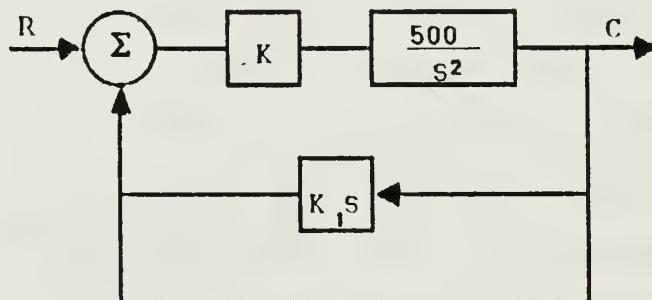


Figure 4-1
Ideal Instrument Servo with Velocity Feedback

Design requirements specify:

Maximum Overshoot M_{pt} (step input) < 20%

Settling Time T_s < 2 sec

Applying Equations (4-1) and (4-2) with design specifications to solve for zeta and omega_n yields:

$$\zeta \geq .46 \quad (4-8)$$

$$\omega_n \geq 4.35 \text{ rad/s} \quad (4-9)$$

Let:

$$a = KK_1 \quad (4-10)$$

$$\beta = K \quad (4-11)$$

The characteristic equation for this system is then:

$$s^2 + 500as + 500\beta = 0 \quad (4-12)$$

Run the parameter plane program by typing in the executable file name, PARAPLAN, when in the subdirectory under which it resides. The IBM microcomputers in the NPS Controls Lab are set up under the file management system 1DIR. To execute the program under this system, enter the appropriate subdirectory by using the up/down arrow keys to position the cursor adjacent to the subdirectory name then depress the ENTER key. Use this same procedure to select PARAPLAN.EXE and push ENTER to run the program.

The LOAD/INSERT Menu will appear. Select Option 2, INPUT Characteristic Equation. Enter coefficient array values after each prompt as follows:

```
'CONSTANT Coefficient of s**2 =' 1
'CONSTANT Coefficient of s**1 =' 0
'CONSTANT Coefficient of s**0 =' 0

'ALPHA Coefficient of s**2 =' 0
'ALPHA Coefficient of s**1 =' 500
'ALPHA Coefficient of s**0 =' 0

'BETA Coefficient of s**2 =' 0
'BETA Coefficient of s**1 =' 0
'BETA Coefficient of s**0 =' 500
```

As this is the first example, let's view the parameter plane over the entire range of zeta. After entering the coefficient array, the program sequences to MAIN Menu. Select Option 1, CURVE Selection Menu. Choose any of the curve data point display options as the next menu appears. Option 1 of the CURVE Selection Menu allows selection of constant zeta curves while Options 2 and 3 provide this service for constant omegan and constant zeta-omegan curves. Input a range of zeta values from zero through one and a range of omegan values from one through ten. Input a value of 2 for the zeta-omegan curve. Select Option 5 to plot the designated curves. The PLOTTING Menu now appears. Either Option 1 or 2 will start the constant curve plotting calculations and subsequently display the plots. The following graphs were obtained by selecting Option 1 and titling the curves.

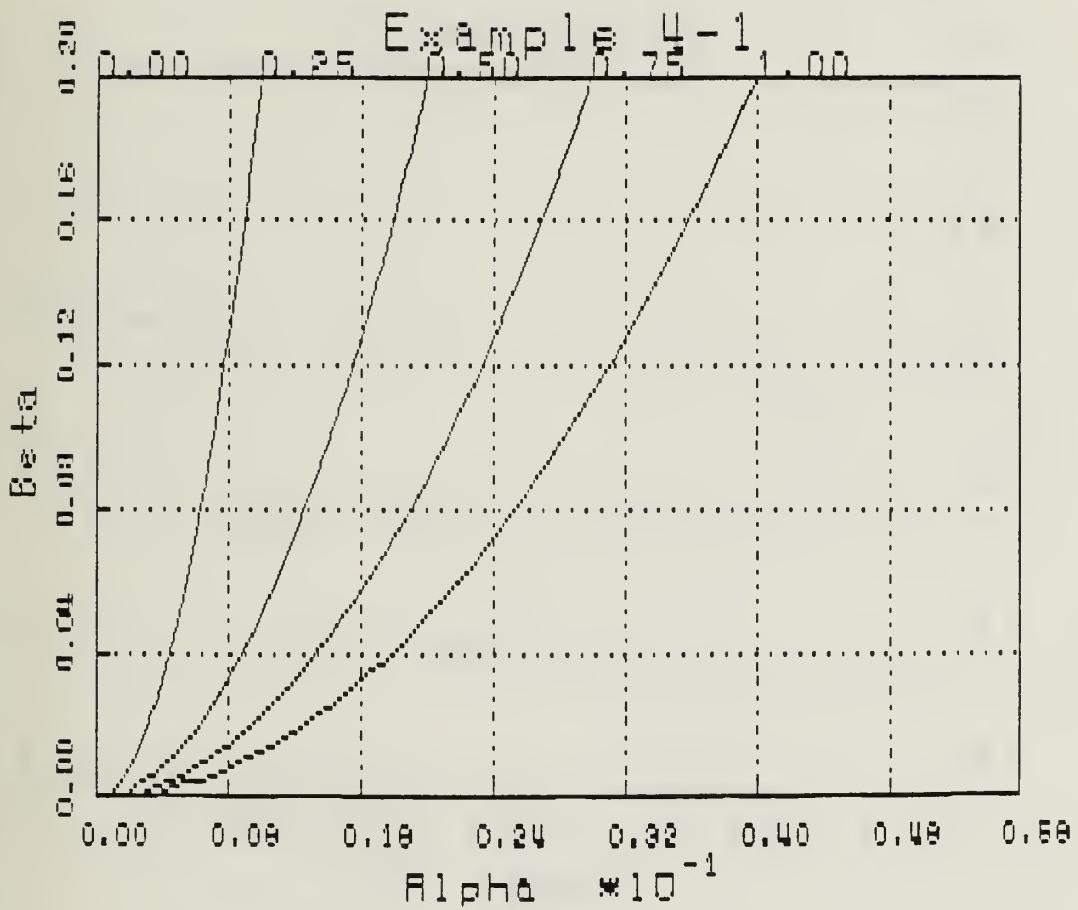


Figure 4-2
Constant Zeta Curves

Example 4-1

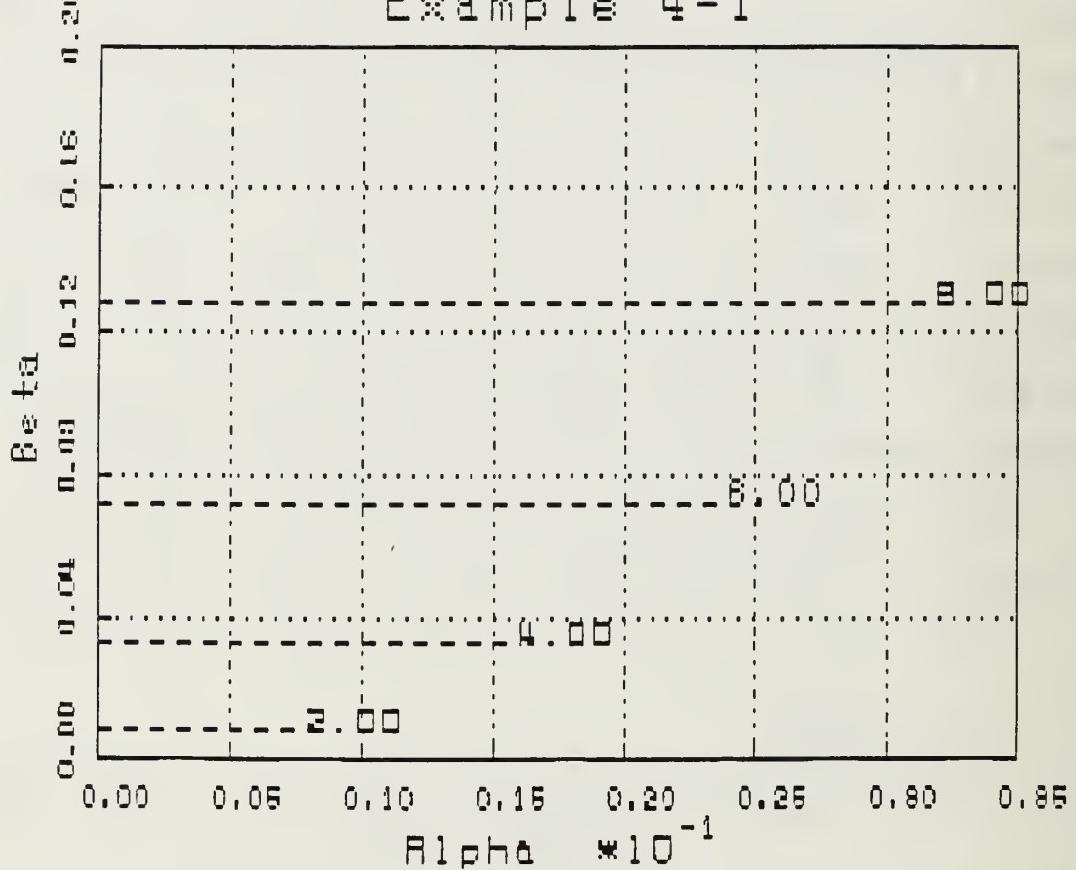


Figure 4-3
Constant Omega Curves

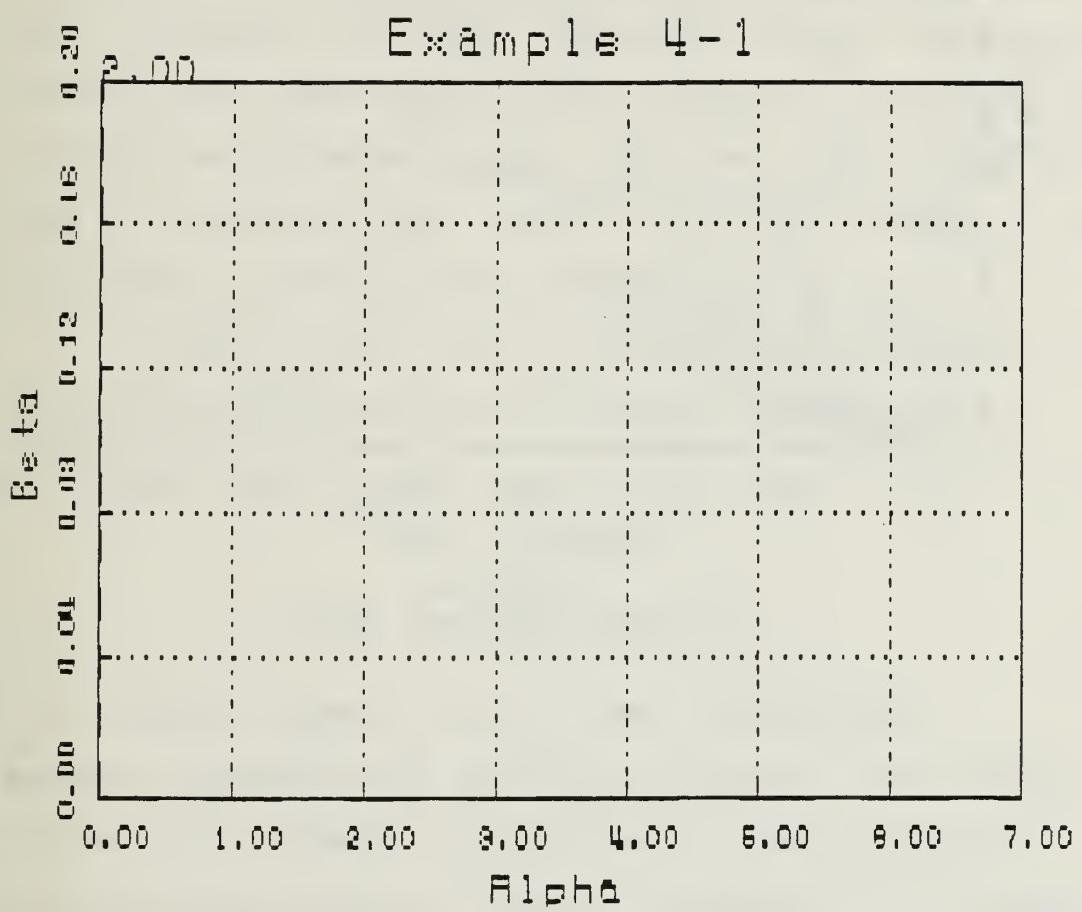


Figure 4-4
Constant Zeta-Omegagan Curve

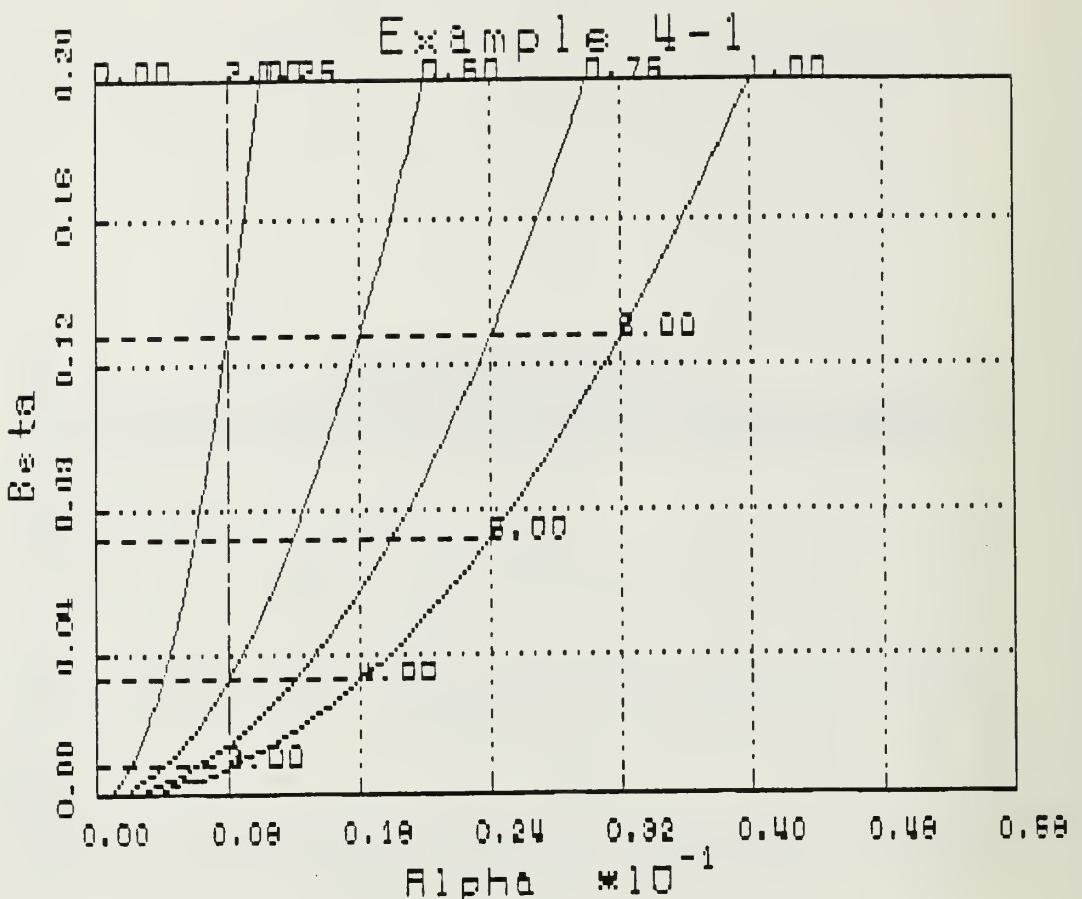


Figure 4-5
Constant Combined Curves

As expected due to the stable nature of this system, all curves are in the first quadrant because all coefficients must be positive to provide roots in the left half of the s-plane. A stable system requires compliance with this condition, although the condition alone does not guarantee stability.

At this point, we could select an option from the expansion menu to better determine the corresponding alpha and beta values satisfying our calculated zeta and omega

parameters. However, we can more precisely determine these values by plotting the actual desired zeta and omegan curves.

Exit from the Plotting Module. An option to save the contour values is offered but not necessary at this point. Reselect the CURVE Selection Option and enter the desired zeta and omegan curves. Equation (4-2) indicates that the zeta-omegan product must be greater than two to keep the settling time below two seconds. Therefore, also select for plotting a zeta-omegan curve of two.

Applying the previously discussed procedures for producing a plot provides the graph of Figure 4-6.

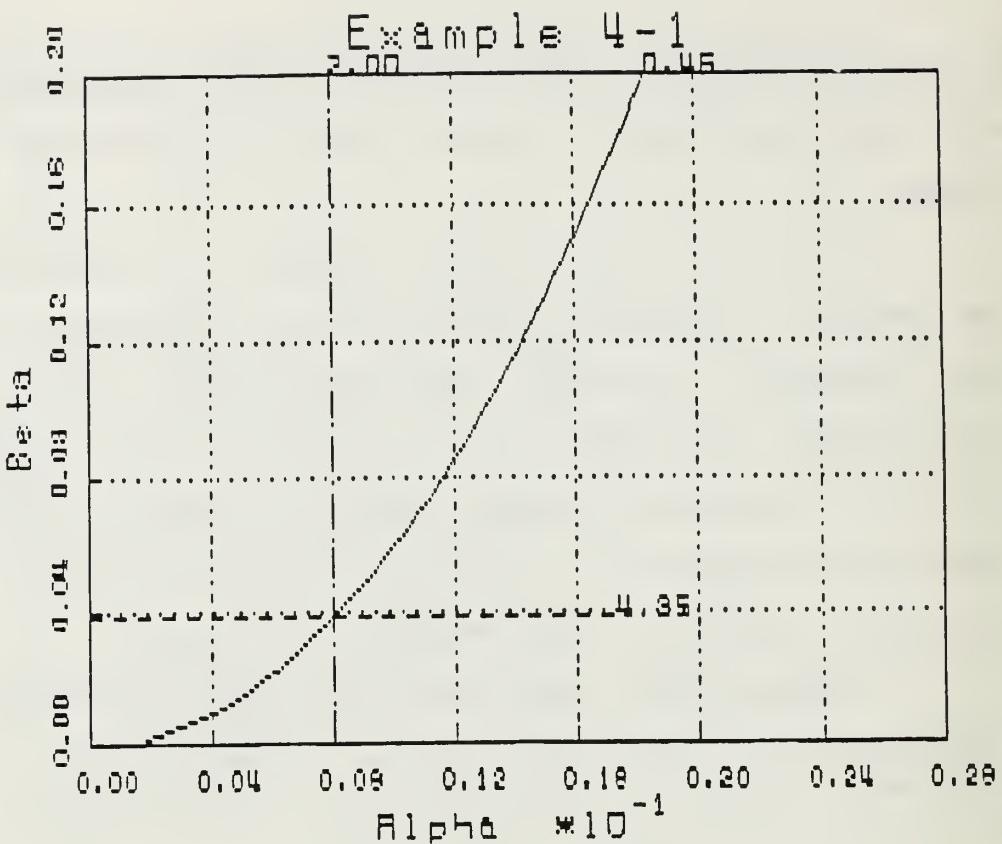


Figure 4-6
 $s^{**2} + 500As + 500B$

All alpha/beta pairs falling to the left of the zeta-omegan curve satisfy the given settling time design requirement. The alpha/beta pair that just meets all requirements is the intersection of the three contours. This value can more accurately be determined by expanding around the position of this point. Using Option 1 of the expansion menu and inserting an alpha range from .006 to .010 and a beta range from .02 to .06 yields the following plot:

Example 4-1

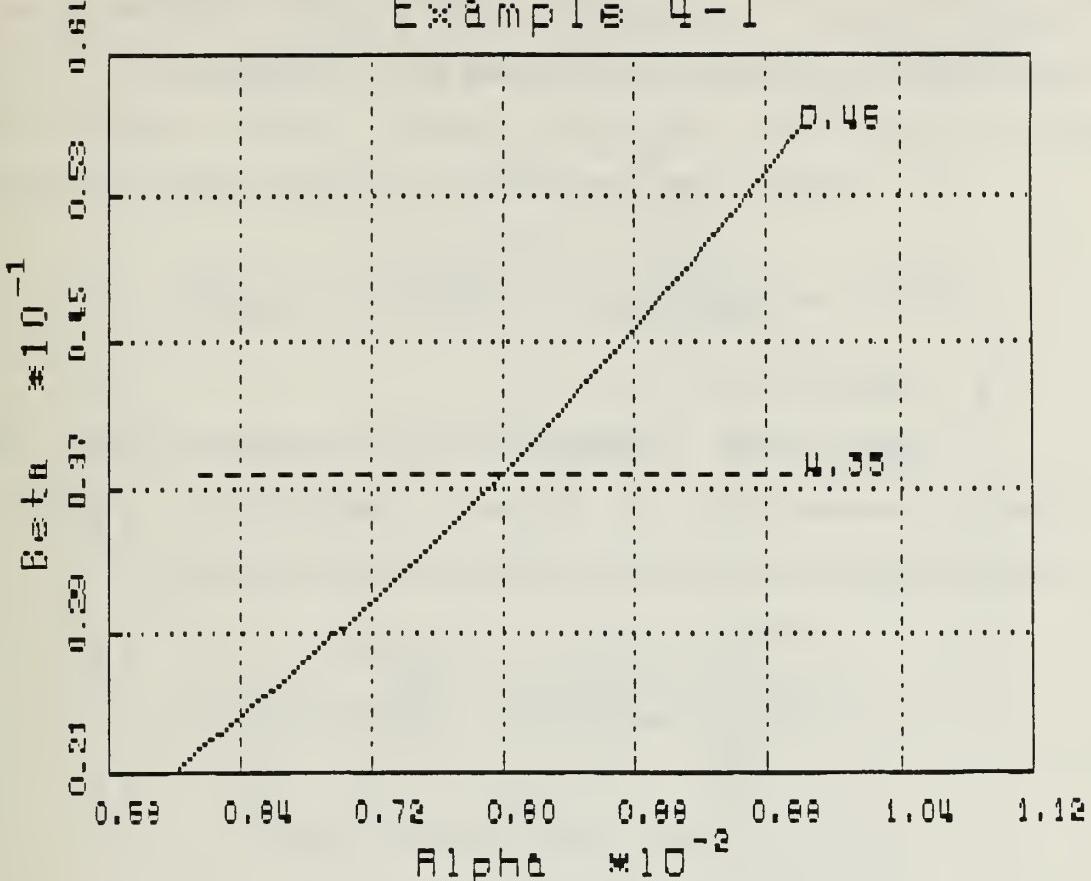


Figure 4-7
 $s^{**2} + 500As + 500B$

The alpha and beta values determined from the preceding graph are:

$$\alpha = .008 \quad (4-13)$$

$$\beta = .038 \quad (4-14)$$

Therefore: $K = .038$ and $K_1 = .211$

A determination of associated closed loop root values for this alpha/beta pair can be accomplished by selecting Option 8, ROOT Finder, in MAIN Menu. At the

prompt, enter the alpha and beta values. Confirming system stability, the outputted system root values are:

COEF(3) = 1.00

COEF(2) = 4.00

COEF(1) = 19.0

First Root = -2.00 + j 3.87
 Second Root = -2.00 - j 3.87

2. Example 4-2

The system response of the previous plant could also be shaped with a cascade compensator. Figure 4-4 illustrates the block diagram of such a system.

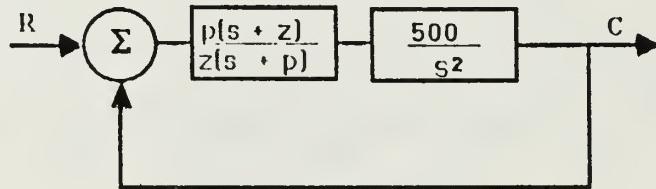


Figure 4-8
 Ideal Instrument Servo with Cascade Compensator

The same procedures apply for deriving the parameter values associated with a particular desired system response.

Let:

$$\alpha = \frac{p}{z} \quad (4-15)$$

$$\beta = p \quad (4-16)$$

The characteristic equation for this system is then:

$$s^3 + \beta s^2 + 500\alpha s + 500\beta = 0 \quad (4-17)$$

Since this is our first look at a third order system, a selection of zeta curves ranging from zero to one and omega curves ranging from one to ten was again selected. The following graph was the result.

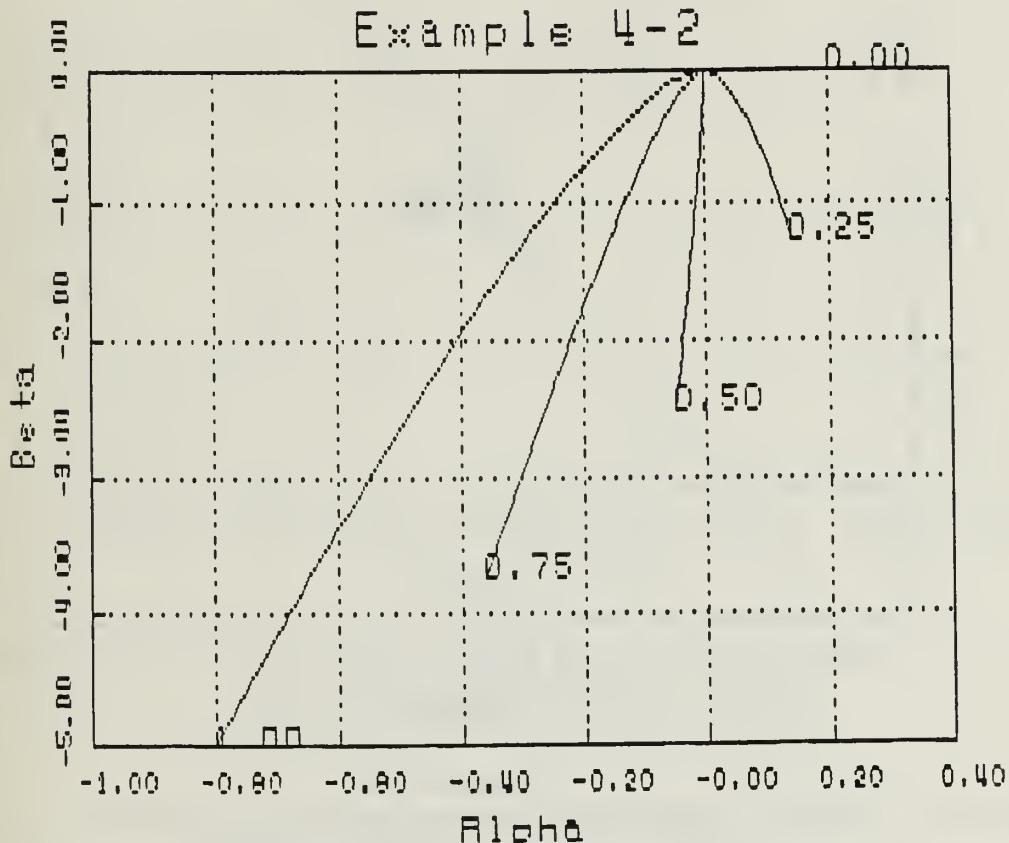


Figure 4-9
 Constant Zeta Curves
 $s^{**3} + Bs^{**2} + 500As + 500B$

As can be seen, most alpha/beta values are negative over the selected frequency range from 1 to 10 rad/s. Both parameters must be positive to provide all closed loop roots in the left half of the s-plane. Therefore, an alteration in frequency range is indicated. A range

spanning 10 to 40 rad/s was entered with the following results:

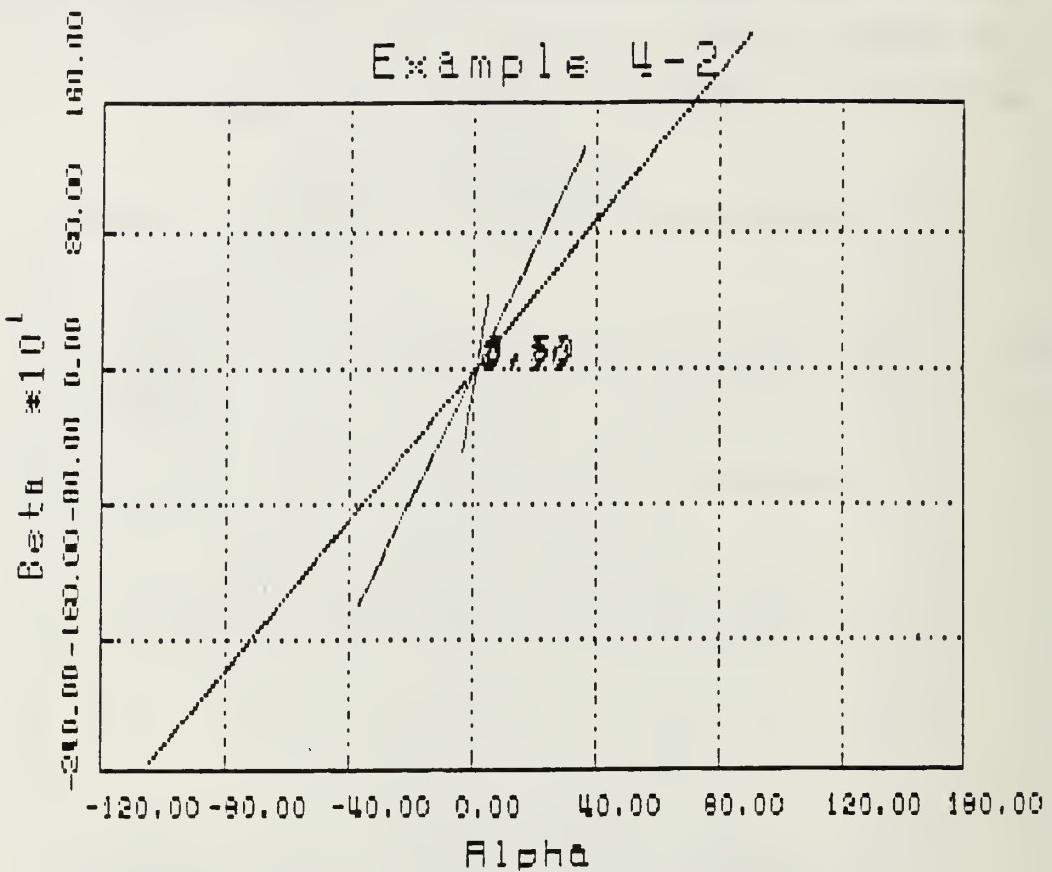


Figure 4-10
Constant Zeta Curves
 $s^{**3} + Bs^{**2} + 500As + 500B$

It can now be seen that positive alpha/beta point pairs are possible, indicating that a stable system can be designed. However, specification limits cannot be met precisely due to the increased natural undamped frequency required. Figure 4-11 presents the zeta and omega contours over a frequency range of 20 to 50 rad/s.

Example 4-2

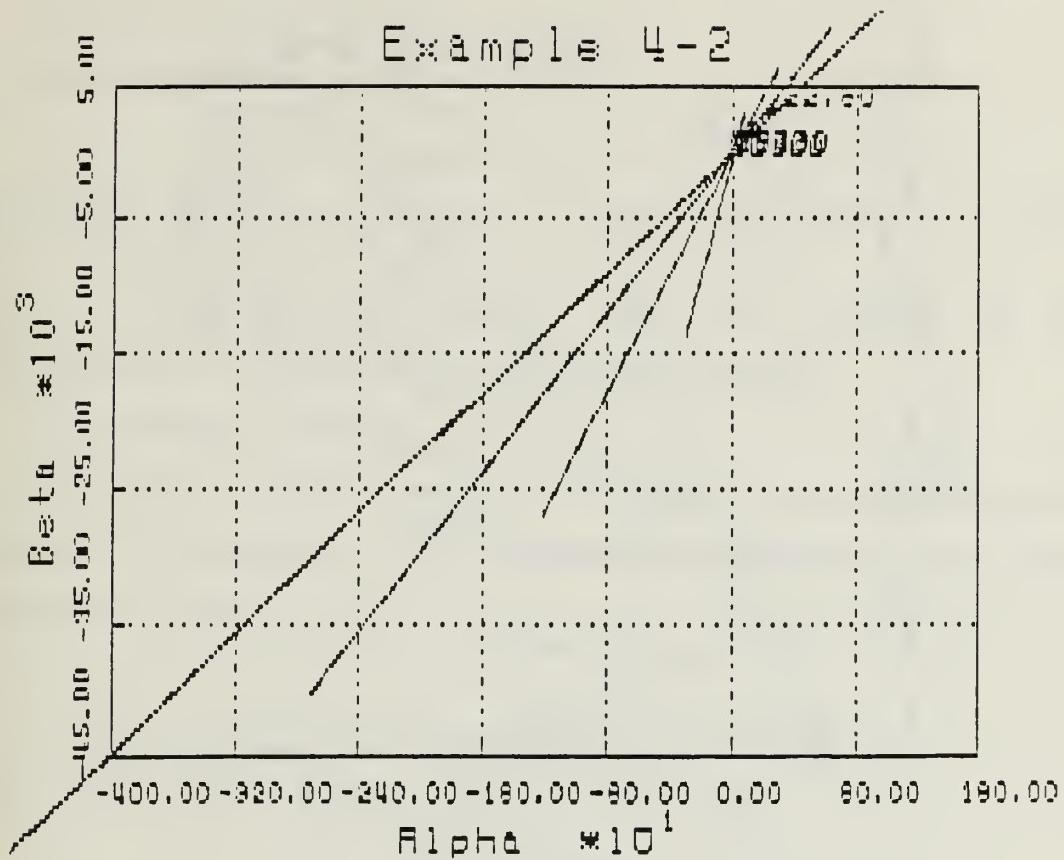


Figure 4-11
Constant Zeta & Omegan Curves
 $s^{**3} + Bs^{**2} + 500As + 500B$

Expanding about an alpha range of zero to ten and beta range of zero to 200 yields a more easily interpreted graph as seen in Figure 4-12.

Example 4-2

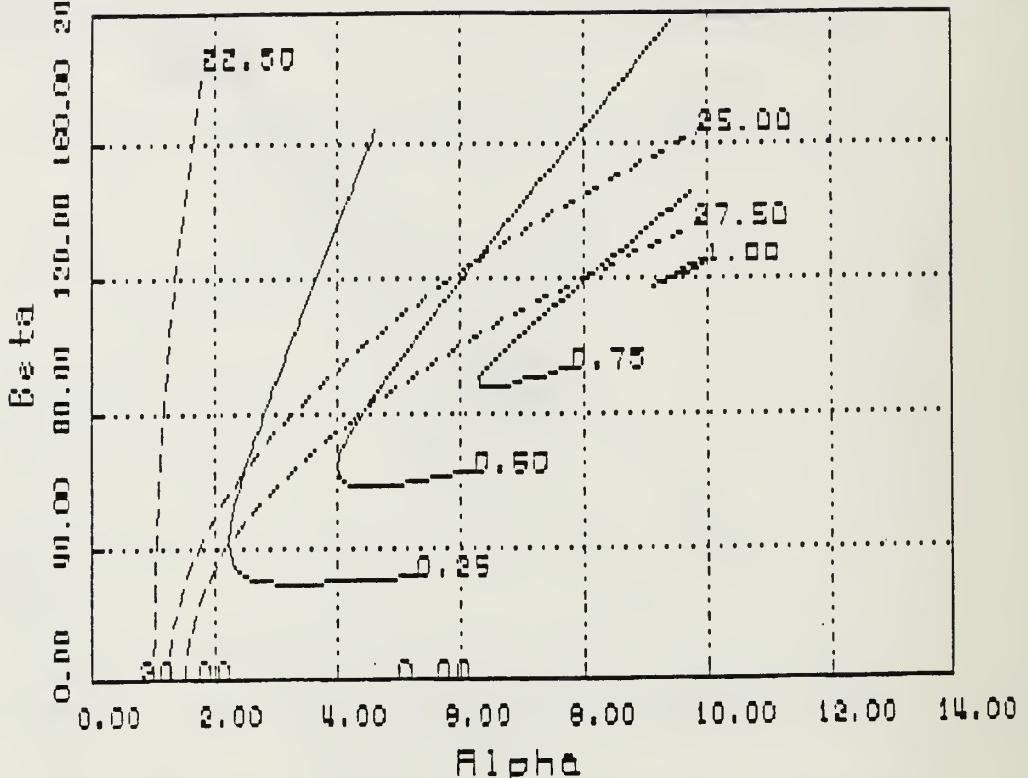


Figure 4-12
Constant Zeta & Omegan Curves
 $s^{**3} + Bs^{**2} + 500As + 500B$

It appears that a minimum omegan value of 25 rad/s is required to maintain an acceptable relative damping coefficient. Selecting an operating point where zeta equals .5 and omegan equals 25 rad/s provides the alpha/beta pair:

$$\alpha = 6.3 \quad (4-18)$$

$$\beta = 125 \quad (4-19)$$

This corresponds to a compensator with a pole at 125 rad/s and a zero at 19.8 rad/s. The resulting closed loop roots with this set of parameters is:

```

COEF( 4) = 1.00
COEF( 3) = 125.
COEF( 2) = .315E+04
COEF( 1) = .625E+05
Root( 3) = -12.65      + j   21.61           Root( 2) = -12.65      - j   21.61
Root( 1) = -99.69      + j   .0000

```

Thus, a clear set of dominant roots is present and all roots reside in the left half of the s-plane.

3. Example 4-3

This example deals with a plant incorporating both velocity (tachometer) and acceleration feedback. The block diagram of such a system is depicted in Figure 4-13.

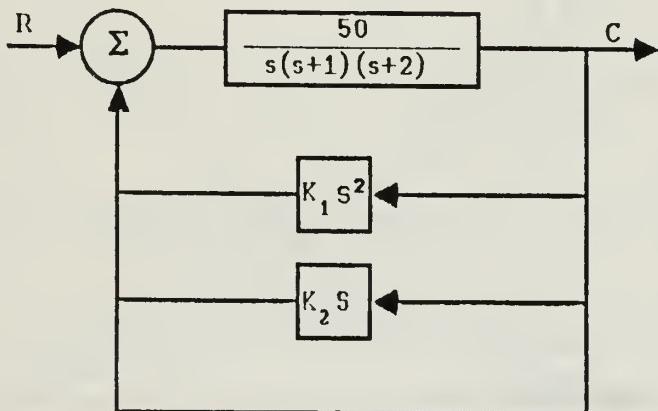


Figure 4-13
Velocity and Acceleration
Feedback Compensated System

The characteristic equation for this system is:

$$s^3 + (3 + 50\alpha)s^2 + (2 + 50\beta)s + 50 = 0 \quad (4-20)$$

where:

$$\alpha = K_1 \quad (4-21)$$

$$\beta = K_2 \quad (4-22)$$

Rather than beginning with a required set of system responses, system options will first be examined to determine possible zeta and omegan values. Figure 4-14 provides a look at the combined zeta and omegan graph spanning a frequency range from one to 100 rad/s.

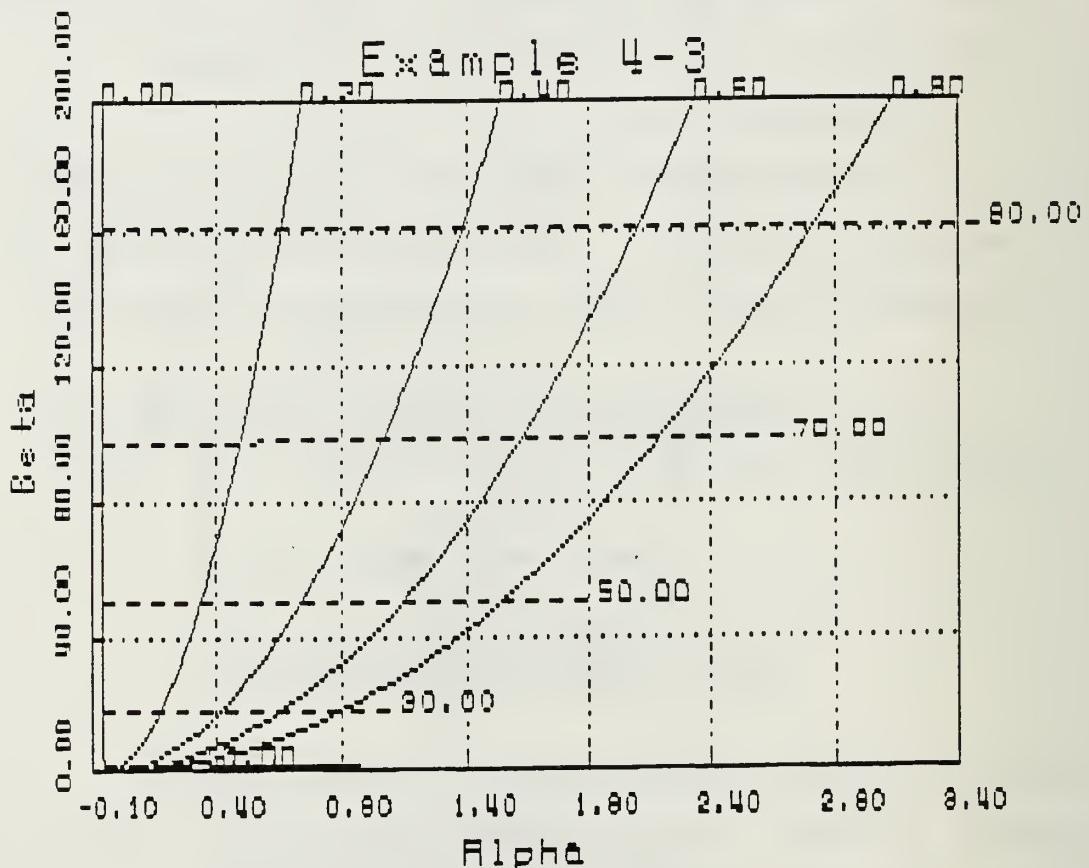


Figure 4-14
Constant Zeta & Omegan Curves
 $s^{**3} + (3+50A)s^{**2} + (2+50B)s + 50$

This system appears to be stable over this frequency range. Design specifications requiring a settling time under one tenth of a second with an overshoot not to exceed ten percent translate into:

$$\zeta \geq .57 \quad (4-23)$$

$$\omega_n \geq 70 \text{ rad/s} \quad (4-24)$$

Reentering the CURVE Selection Menu and adjusting the frequency range to 60-80 rad/s, while specifying curves of zeta equals .55, .57 and .60 and omegan equals 65, 70 and 75 rad/s, produces the plot of Figure 4-15.

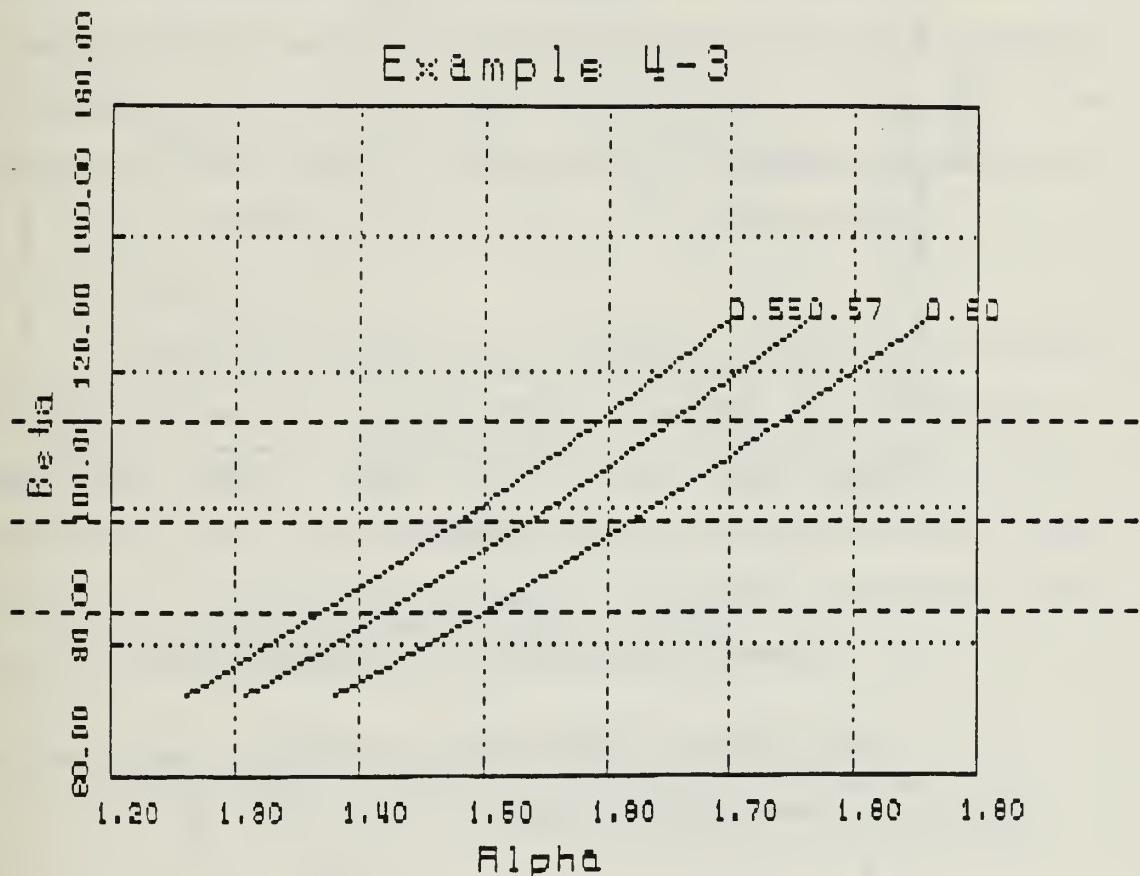


Figure 4-15
Constant Zeta & Omegan Curves
 $s^{**3} + (3+50A)s^{**2} + (2+50B)s + 50$

Expanding about the desired operating point yields:

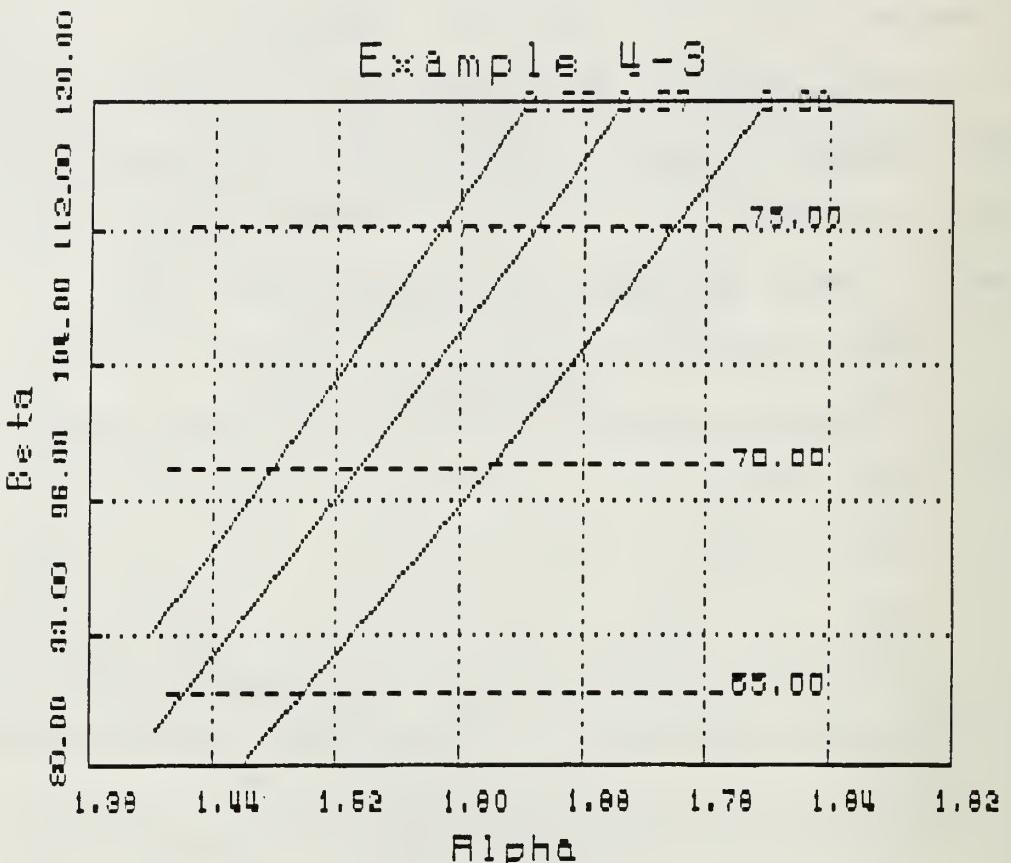


Figure 4-16
Constant Zeta & Omegan Curves
 $s^{**3} + (3+50A)s^{**2} + (2+50B)s + 50$

From Figure 4-16, alpha and beta can be easily extracted. Their values are:

$$\alpha = 1.635 \quad (4-25)$$

$$\beta = 98.0 \quad (4-26)$$

Thus the acceleration feedback coefficient, K₁, is 1.635 and the corresponding velocity feedback coefficient, K₂, is 98.0. These values provide root locations of:

```

COEF( 4) = 1.00
COEF( 3) = 84.8
COEF( 2) = .490E+04
COEF( 1) = 50.0
Root( 3) = -42.37 + j 55.73           Root( 2) = -42.37 - j 55.73
Root( 1) = -.1020E-01 + j .0000

```

Obviously, the dominant roots are not at the designed locations. The dominant real root and relatively distant complex roots indicate that the system is probably overdamped. The omega value chosen in an attempt to force a short settling time is too large. A redesign is indicated if a longer settling time can not be accommodated.

4. Example 4-4

The final example will examine a forth order system to demonstrate the difficulty involved in choosing an alpha/beta pair from a set of convoluted contours associated with higher order systems. A third order, type one plant will be shaped with a cascade compensator. The system block diagram is illustrated in Figure 4-17.

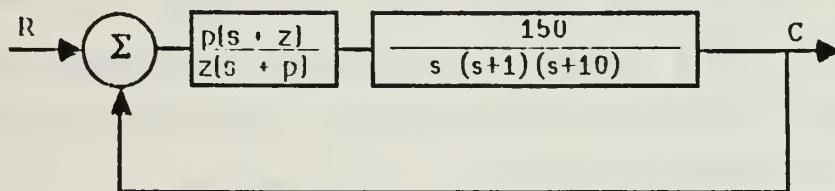


Figure 4-17
Third Order, Type One System
With Cascade Compensation

The characteristic equation for this system is:

$$s^4 + (11 + \beta)s^3 + (10 + 11\beta)s^2 + (150\alpha + 10\beta)s + 150\beta = 0 \quad (4-27)$$

where:

$$\alpha = \frac{p}{z} \quad (4-28)$$

$$\beta = p \quad (4-29)$$

System specifications call for:

$$\text{Peak Overshoot} < 50\%$$

$$\text{Settling Time} < 1 \text{ second}$$

The corresponding relative damping coefficient and undamped natural frequency are:

$$\zeta \geq .22 \quad (4-30)$$

$$\omega_n \geq 18.2 \text{ rad/s} \quad (4-31)$$

Based on Equation (4-7), the phase margin of a system with a zeta value of .22 is approximately 20 degrees. Although the system may be stable, it will be very sensitive, especially considering that the resonant peak of this system occurs at about the same frequency as ω_{m} . In any case, with higher order systems it is important to perform a time response simulation to more accurately determine system behavior. Figure 4-18 is a combined plot over a frequency range of 10 to 50 rad/s.

Example 4-4

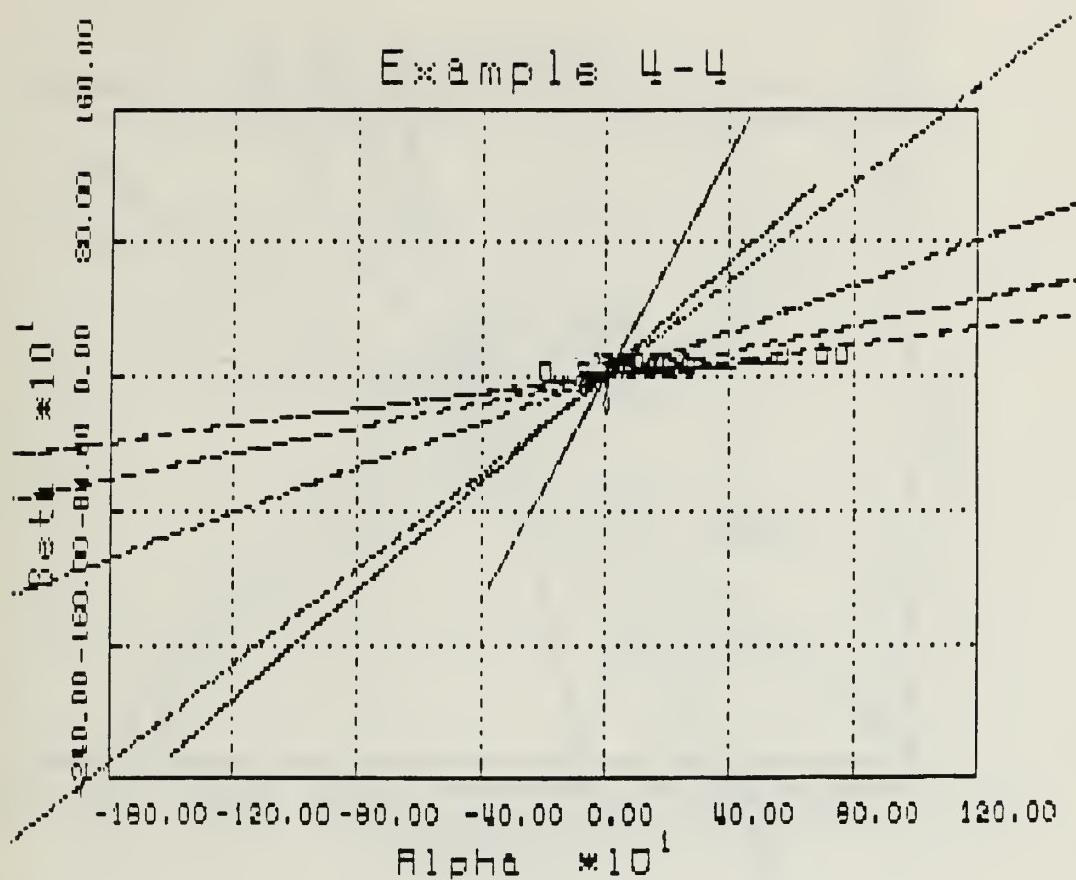


Figure 4-18
Constant Zeta & Omegan Curves
 $s^{**4} + (11+B)s^{**3} + (10+11B)s^{**2}$
 $+ (150A+10B)s + 150B$

There appears to be a lot of activity about the operating point located at zero. Figure 4-19 is a result of expanding about that point.

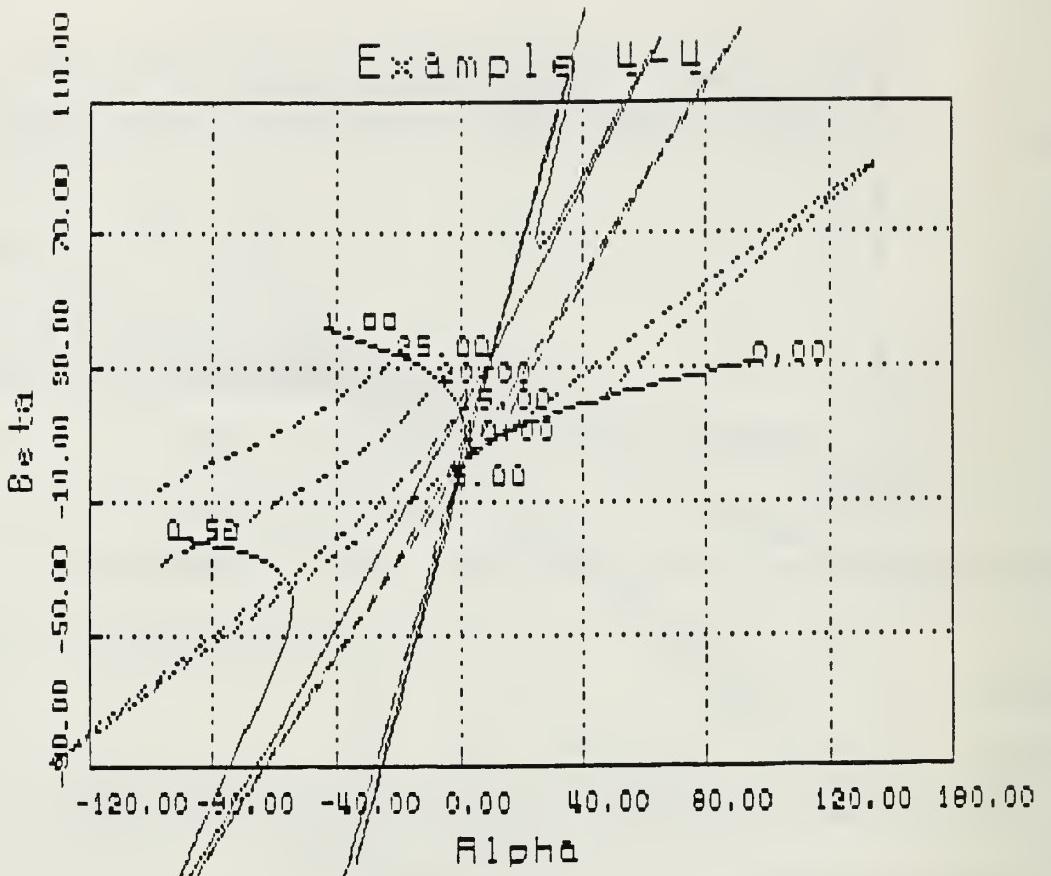


Figure 4-19
 Constant Zeta & Omegan Curves
 $s^{**4} + (11+B)s^{**3} + (10+11B)s^{**2}$
 $+ (150A+10B)s + 150B$

It is apparent that higher order plots are not as well behaved as the lower order systems. To reduce confusion and make the graph more readable, fewer contours must be selected. Reducing the range of frequencies to a span from 10 to 20 rad/s and selecting three zeta and two omega curves about the desired operating point produces the following graph.

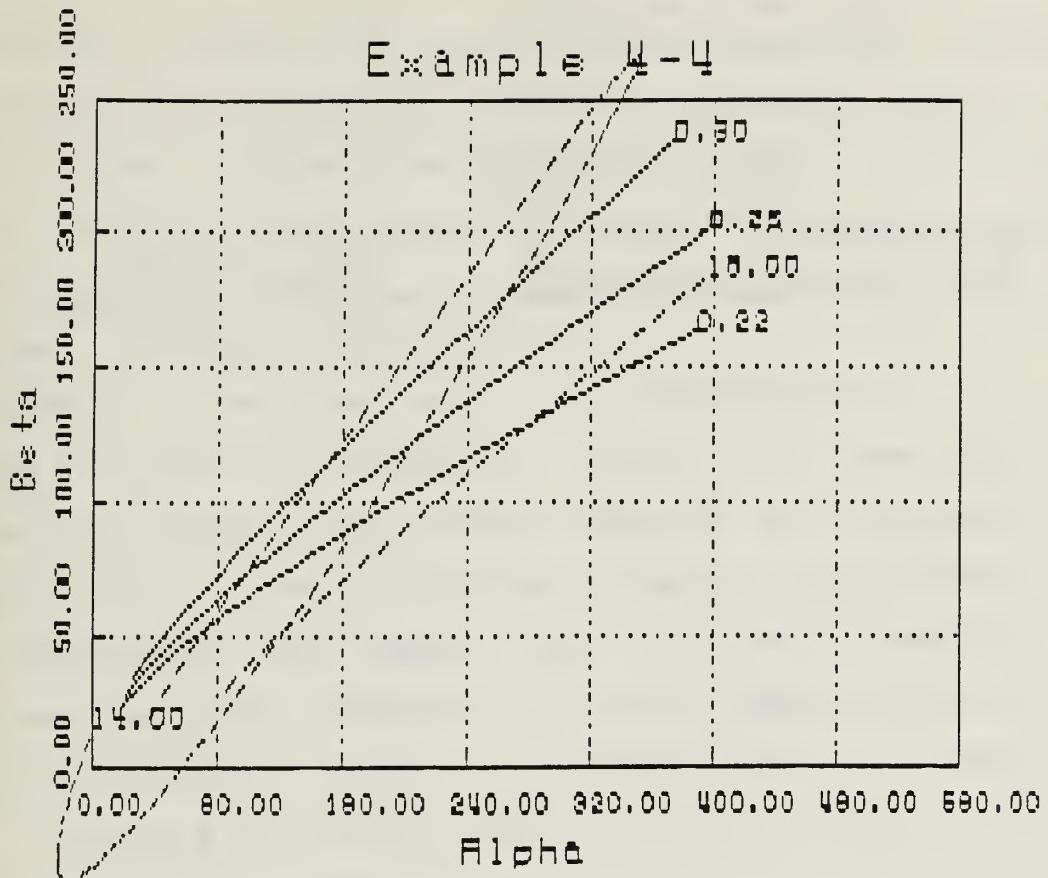


Figure 4-20
 Constant Zeta & Omegan Curves
 $s^{**4} + (11+B)s^{**3} + (10+11B)s^{**2}$
 $+ (150A+10B)s + 150B$

The alpha/beta pair associated with zeta equals .22 and omegan equals 18.0 follows:

$$\alpha = 280 \quad (4-32)$$

$$\beta = 130 \quad (4-33)$$

The roots derived through application of these values are:

```

COEF( 5) = 1.00
COEF( 4) = 141.
COEF( 3) = .144E+04
COEF( 2) = .433E+05
COEF( 1) = .195E+05

Root( 4) = -3.975 + j 17.49      Root( 3) = -3.975 - j 17.49
Root( 2) = -.4570 + j .0000      Root( 1) = -132.6 - j .0000
Pause - Please enter a blank line (to continue) or a DOS command.

```

Unfortunately, with that particular selection of alpha and beta values, a dominant real root is present. Examination of the step input time response indicates an overshoot of 50% and a settling time of 1.2 seconds. An increase in zeta to better dampen the system results in a decreased omegan term if the system settling time is to remain at approximately one second. A zeta value increase to .3 with an associated omegan value of 14 yields:

$$a = 150 \quad (4-34)$$

$$\beta = 115 \quad (4-35)$$

```

COEF( 5) = 1.00
COEF( 4) = 126.
COEF( 3) = .128E+04
COEF( 2) = .237E+05
COEF( 1) = .173E+05

Root( 4) = -4.218 + j 13.30      Root( 3) = -4.218 - j 13.30
Root( 2) = -.7591 + j .0000      Root( 1) = -116.7 - j .0000
Pause - Please enter a blank line (to continue) or a DOS command.

```

The complex roots have made a relative shift in the s-plane toward the dominant real root. Once again, however, it can be difficult with high order systems to make a

definitive judgment on system behavior without viewing transient time response curves. The unit step response of this system provides a maximum overshoot of 40% with a one second settling time. Thus, a cascade compensator with a gain of 150, a zero at 0.76 and a pole at 115 provides a suitable transient response.

V. CONCLUSIONS AND RECOMMENDATIONS

A. CONCLUSIONS

As has been demonstrated, rapid solution of a wide range of linear automatic control systems problems can be achieved through use of the parameter plane program developed as part of this thesis. An IBM compatible microcomputer program offers the inherent advantages of portability and ready access to machines capable of supporting the code.

The graphical solution of the parameter plane technique provides the designer with a visual means of deducing how the dominant roots of the characteristic equation move about in the s-plane as two user defined parameters defining compensator attributes are varied. As a corollary, input of specific system response characteristics can be made to determine the parameter values providing that response. In addition, the parameter plane design procedure is independent of system configuration since it deals with the characteristic equation only.

There are some drawbacks to this technique. Only two variables can presently be considered in the computer model. However, a three variable parameter space method could be developed. In place of a series of curves in the two dimensional case, the parameter space graphical output

would be represented by a surface in three dimensions. Another shortcoming associated with the parameter plane analysis method is that information on open loop poles and zeros is not available.

B. RECOMMENDATIONS FOR FURTHER STUDY

The most significant addition that could be made to the parameter plane program would be the incorporation of a graphical cost function analysis package. In a linear feedback control system, the difference between the input to the system and its output is termed the error. This error differs with differing compensators. In most cases involving automatic feedback control systems, minimization of the error over a certain period of time (e.g., twice the settling time) is desired. Minimization of other system attributes is also common. One may wish to minimize the absolute value of the error, the square of the error or any one of an infinite number of cost functions, depending on the particular system application. Constant cost value contours can be plotted in much the same presentation as the parameter plane plot. Using standardized scales, desired system response characteristics can be compared with the error cost at that operating point and a suitable compromise between minimum cost and desired system response can be reached.

An alternative presentation method is available with the plotting package currently used by the parameter plane program. The cost value associated with a particular pair of alpha/beta values could be plotted as the third dimension of a parameter space surface. Although precise determination of the three variable values would be difficult, a quick synopsis of system response trends would be available. This would permit ready localization of interesting operating areas for more refined analysis on a two dimensional plot.

APPENDIX
PARAMETER PLANE PROGRAM

```
C
C =====
C          PARAMETER PLANE PROGRAM
C =====
C
$NOfloatcalls
      Program ParaPlan
      dimension CONST(10),ALPHA(10),BETA(10),A(1002),B(1002),ZETA(10),
*           WN(10),AOMEGA(1002),BOMEGA(1002),ZWN(10),AZTAOM(1002),
*           BZTAOM(1002)
      real R,WNMIN,U,U1,U2,B1,B2,C1,C2,D1,D2,CONST,ALPHA,BETA,A,B,ZETA,
*           WN,AOMEGA,BOMEGA,WNMAX,WNMIN1,ALPHA1,BETA1,ZWN,AZTAOM,
*           BZTAOM,INCZWN
      integer SEL,SEL3,ORDER,NUMCOF,NUMZTA,I,M,N,K,L,J,ROW2,COLM,
*           IOPORT,MODEL,START,STOP,FLAG,NUMWN,STOPO,FLAGRT,CURV,
*           NUMZWN,STOPZO,OUT
      character*12 FILEIN,FILEOUT
      common A,B,AOMEGA,BOMEGA,AZTAOM,BZTAOM
      common/plottr/ IOPORT,MODEL
      data FLAGRT/0/
C
      IOPORT = 99
      MODEL = 99
      OUT = 3
      R = 10.
10   call INTRMN (SEL)
      if ((SEL .eq. 4) .or. (SEL .eq. 6) .or. (SEL .eq. 10)) go to 4
1   call MAINMN (SEL)
4   FLAG = 0
3   if (SEL .eq. 1) then
        call CRVSEL (CONST,ALPHA,BETA,ZETA,NUMZTA,STOP,NUMCOF,
*                      WNMIN,WNMAX,FLAG,SEL,NUMWN,WN,
*                      STOPO,ORDER,ZWN,NUMZWN,STOPZO)
      else if (SEL .eq. 2) then
        call MONPRT
      else if (SEL .eq. 3) then
        call REVCHG (ORDER,NUMCOF,CONST,ALPHA,BETA,WNMIN,WNMAX,SEL,FLAG)
      else if (SEL .eq. 4) then
        call LDFILE (ORDER,NUMCOF,CONST,ALPHA,BETA,WNMIN,WNMAX)
      else if (SEL .eq. 5) then
        call SAVFIL (ORDER,NUMCOF,CONST,ALPHA,BETA,WNMIN,WNMAX,FILEOUT)
      else if (SEL .eq. 6) then
        call CHAREQ (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,WNMAX,FLAGRT,
*                      ALPHA1,BETA1)
```

```

else if (SEL .eq. 7) then
    call RUNPRO (NUMZTA,STOP,ZETA,CURV,NUMWN,WN,
*                      STOPO,ZWN,NUMZWN,STOPZO)
else if (SEL .eq. 8) then
    FLAGRT = 1
    call ROOTS (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,WNMAX,
*                      ALPHA1,BETA1,FLAGRT,OUT,R)
    PAUSE
    FLAGRT = 0
else if (SEL .eq. 10) then
    call SAMPLE
    goto 10
else
    go to 999
2 end if
if (FLAG .eq. 1) go to 4
go to 1
999 stop
end
end

C
C
C ****
C          USER UTILITIES MODULE
C ****
C
C =====
C Subroutine INTRMN -- allows input of C. E. from file or keyboard
C =====
C
Subroutine INTRMN (SEL)
integer SEL
78  call CLR
    write(*,80)
    write(*,81)
    write(*,82)
    write(*,81)
    write(*,83)
    write(*,81)
    write(*,93)
80  format(1x,////////,10x,'-----
*-----',/,10x,'|',22x,'LOAD/INSERT MENU',24x,'|')
81  format(10x,'-----
*-----')
82  format(10x,'|',2x,'OPTION NO.',2x,'|',20x,'OPTION',21x,'|')
83  format(10x,'|',2x,'     1      ',2x,'|',5x,'LOAD Problem from File',
```

```

*20x,'|
*,/10x,'|',2x,'      2      ',2x,'|',5x,'INPUT Characteristic Equatio
*n',13x,'|'
*,/10x,'|',2x,'      3      ',2x,'|',5x,'EXAMPLE Characteristic Equat
ion Input',5x,'|'
*,/10x,'|',2x,'      9      ',2x,'|',5x,'EXIT to Main Menu',25x,'|')
93  format(1x,///,15x,'Enter integer number for selection ===> ')
call PSIT(22,56)
read(*,* ,err=78) SEL
if (SEL .eq. 1) then
  SEL = 4
else if (SEL .eq. 2) then
  SEL = 6
else if (SEL .eq. 3) then
  SEL = 10
else
  continue
end if
return
end
end

C
C =====
C Subroutine MAINMN -- allows selection of items from the main menu
C =====
C
Subroutine MAINMN (SEL)
integer SEL
79  call CLR
write(*,80)
write(*,81)
write(*,82)
write(*,81)
write(*,83)
write(*,81)
write(*,84)
write(*,81)
write(*,85)
write(*,87)
write(*,86)
write(*,81)
write(*,93)
80  format(1x,/,10x,'-----
*-----',/,10x,'|',25x,'MAIN MENU',28x,'|')
81  format(10x,'-----
*-----')

```

```

87  format(10x,'+++++++++++++++++++++++++++++++++++++++')
*+++++++
82  format(10x,'|',2x,'OPTION NO.',2x,'|',20x,'OPTION',21x,'|')
83  format(10x,'|',2x,'    1      ',2x,'|',5x,'CURVE Selection Menu',
*22x,'|'
*.,10x,'|',2x,'    2      ',2x,'|',5x,'PRINTER Selection Menu'
*.,20x,'|'
*.,10x,'|',2x,'    3      ',2x,'|',5x,'REVIEW/CHANGE Selections'
*.,18x,'|')
84  format(10x,'|',2x,'    4      ',2x,'|',5x,'LOAD Problem from File',
*20x,'|'
*.,10x,'|',2x,'    5      ',2x,'|',5x,'SAVE This Problem',
*25x,'|'
*.,10x,'|',2x,'    6      ',2x,'|',5x,'INPUT Characteristic Equatio
*n',13x,'|')
85  format(10x,'|',2x,'    7      ',2x,'|',5x,'PLOT Curves',31x,'|'
*.,10x,'|',2x,'    8      ',2x,'|',5x,'ROOT Finder',31x,'|')
86  format(10x,'|',2x,'    9      ',2x,'|',5x,'EXIT Program',30x,'|')
93  format(1x,///,15x,'Enter integer number for selection ==> ')
call PSIT(24,56)
read(*,*,err=79) SEL
return
end

C
C =====
C Subroutine LDFILE -- allows loading of data from an existing file
C =====
C
Subroutine LDFILE (ORDER,NUMCOF,CONST,ALPHA,BETA,WNMIN,WNMAX)
real WNMIN,WNMAX,CONST(10),ALPHA(10),BETA(10)
integer ORDER,NUMCOF,MODEL,IOPORT,TEST,I
character*12 FILEIN,ANS*1
logical EXIST
common/plottr/ IOPORT,MODEL
1 call CLR
write(*,100)
100 format(1x,///,10x,'-----
*-----',./,10x,'*** This is the routine to LOAD data from a file **'
**',./,10x,'-----
*.,./,10x,'File name should not exceed 8 characters',/,
*10x,'File extension should not exceed 3 characters')
write(*,101)
101 format(1x,///,10x,'What is the file name (fn) and extension (ext)
*? ',./,10x,'Enter in form fn.ext (e.g. PARAPLAN.INP) ==> ')
call PSIT(18,57)
read(*,102) FILEIN

```

```

102 format(a12)
    inquire(file=FILEIN,exist=EXIST)
    if (EXIST) then
        open(7,FILE=FILEIN,STATUS='OLD',ACCESS='SEQUENTIAL')
    else
        write(*,103)
103    format(///,10x,'That file does not exist.',/,10x,
*           'Do you want to try again? (Y/N)')
        read(*,'(A1)') ANS
        if((ANS .eq. 'Y') .or. (ANS .eq. 'y')) then
            goto 1
        else
            goto 2
        end if
    end if
    read(7,105) MODEL,IOPORT
    read(7,110) ORDER,NUMCOF
    read(7,115) WNMIN,WNMAX
    do 190 I = 1,NUMCOF
        read(7,120) CONST(I),ALPHA(I),BETA(I)
190    continue
    close(7,STATUS='KEEP')

C
105 format(1x,I2,2X,I2)
110 format(1x,I2,2X,I2)
115 format(1x,2F15.7)
120 format(1x,3F15.7)
    write(*,3) WNMIN,WNMAX,ORDER
3    format(1X,////////,5x,'WNMIN = ',f12.3,5x,'WNMAX = ',f12.3,5x,
*           'ORDER = ',I2,/)
    do 9 I = NUMCOF,1,-1
        J = I - 1
        write(*,4) J,CONST(I),J,ALPHA(I),J,BETA(I)
9    continue
4    format(1X,'CONST(',I2,') = ',f10.3,5x,'ALPHA(',I2,',') = ',f10.3,5x,
*           'BETA(',I2,',') = ',f10.3)
        write(*,5)
5    format(1X,//////)
    PAUSE

C
2    return
end
C

```

```

C =====
C Subroutine SAVFIL -- allows entered data to be saved to a data file
C =====
C
Subroutine SAVFIL (ORDER,NUMCOF,CONST,ALPHA,BETA,WNMIN,WNMAX,
*                   FILEOUT)
real WNMNIN,WNMAX,CONST(10),ALPHA(10),BETA(10)
integer ORDER,NUMCOF,MODEL,IOPORT,TEST,I,J,SEL,SEL3
character*12 FILEOUT,ANS*1
logical EXIST
common/plottr/ IOPORT,MODEL
2 call CLR
write(*,100)
100 format(1x,///,10x,'-----
*----',/,10x,'*** This is the routine to SAVE data to a file ***'
*,/,10x,'-----'
*,//,10x,'File name should not exceed 8 characters',/,
*10x,'File extension should not exceed 3 characters')
write(*,101)
101 format(1x,///,10x,'What is the file name (fn) and extension (ext)
*? ',/,10x,'Enter in form fn.ext (e.g. PARAPLAN.OUT) ===> ')
call PSIT(18,57)
read(*,102) FILEOUT
102 format(a12)
call CLR
inquire(file=FILEOUT,exist=EXIST)
if (EXIST) then
  write(*,103)
103  format(///,10x,'That file already exists.',/,10x,
*           'Do you want to overwrite? (Y/N)')
  read(*,'(A1)') ANS
  if((ANS .eq. 'Y') .or. (ANS .eq. 'y')) then
    open(7,file=FILEOUT,status='OLD')
    rewind 7
    goto 1
  else
    goto 2
  end if
end if
open(7,file=FILEOUT,status='NEW')
1 write(7,105) MODEL,IOPORT
write(7,110) ORDER,NUMCOF
write(7,115) WNMNIN,WNMAX
do 190 I = 1,NUMCOF

```

```

        write(7,120) CONST(I),ALPHA(I),BETA(I)
190  continue
      close(7,STATUS='KEEP')
C
105  format(1x,I2,2X,I2)
110  format(1x,I2,2X,I2)
115  format(1x,2F15.7)
120  format(1x,3F15.7)
      write(*,3) FILEOUT
3    format(1x,/////////,10x,'File name and extension = ',a12,///)
      write(*,4) WNMIN,WNMAX,ORDER
4    format(5x,'WMIN = ',g11.4,5x,'WMAX = ',g11.4,5x,
*           'ORDER = ',I2,/)
      do 9 I = NUMCOF,1,-1
         J = I - 1
         write(*,5) J,CONST(I),J,ALPHA(I),J,BETA(I)
9    continue
5    format(1X,'CONST(‘,I2,’) = ‘,f10.3,5x,’ALPHA(‘,I2,’) = ‘,f10.3,5x,
*           ‘BETA(‘,I2,’) =‘,f10.3)
      write(*,6)
6    format(1x,/////)
      PAUSE
      return
      end
C
C =====
C Subroutine CHAREQ -- allows input of characteristic equation
C =====
C
      Subroutine CHAREQ (ORDER,CONST,ALPHA,BETA,NUMCOF,WMIN,WMAX,
*                      FLAGRT,ALPHA1,BETA1)
      real CONST(10),ALPHA(10),BETA(10),WMIN,WMAX,ALPHA1,BETA1
      integer ORDER,I,NUMCOF,IMIN1,ROW1,FLAGRT
      character*1 CHG
200  call CLR
C
      if (FLAGRT .eq. 1) then
      write(*,190)
190  format(1x,/,9x,'Do you want to find the roots of the existing Cha
*racteristic’,/,9x,’Equation, entering values for ALPHA & BETA?’,
*/,9x,’Enter “y” or “n” ==> ’)
      call PSIT(7,30)
      read(*,’(A)’,err=200) CHG
      end if
      if ((CHG .eq. ‘y’) .or. (CHG .eq. ‘Y’)) then
          go to 293

```

```

    end if
    call CLR
C
C      *** Enter ORDER of Characteristic Equation ***
write(*,201)
201  format(1x,////,10x,'What is the order of the Characteristic Equati
*on? ',//,10x,'Enter integer value less than or equal to 9 ==> ')
call PSIT(8,59)
read(*,*,err=200) ORDER
NUMCOF = ORDER + 1

C
C      *** Enter CONSTANT Coefficients ***
210  call CLR
ROW1 = 10
write(*,211)
211  format(1x,////,5x,'Enter the CONSTANT Coefficient Values of the Ch
*aracteristic Equation',/,5x,'-----'
*-----',/)
do 217 I = NUMCOF,1,-1
    IMIN1 = I - 1
    write(*,220) IMIN1
220  format(1x,/,5x,'CONSTANT Coefficient of S **',I2,' = ')
    call PSIT(ROW1,40)
    read(*,*,err=210) CONST(I)
    ROW1 = ROW1 + 2
217  continue
218  call CLR
    write(*,230)
230  format(1x,////,20x,'***** CONSTANT COEFFICIENTS *****',//)
do 235 I = NUMCOF,1,-1
    IMIN1 = I - 1
    write(*,237) IMIN1,CONST(I)
237  format(26x,'CONST(',I2,') = ',f9.3,/)
235  continue
    ROW1 = ROW1 + 3
    write(*,239)
239  format(1x,/,5x,'Do you want to make any CHANGES to the CONSTANT C
*oefficient Values?',/,5x,'Enter "y" or "n" ==> ')
    call PSIT(ROW1,26)
    read(*,'(A)',err=218) CHG
    if ((CHG .eq. 'y') .or. (CHG .eq. 'Y')) then
        go to 210
    end if
C
C      *** Enter ALPHA Coefficients ***
240  call CLR

```

```

ROW1 = 10
write(*,241)
241 format(1x,///,5x,'Enter the ALPHA Coefficient Values of the Chara
*cteristic Equation',/,5x,'-----'
*-----',/)
do 247 I = NUMCOF,1,-1
  IMIN1 = I - 1
  write(*,250) IMIN1
250 format(1x,/,5x,'ALPHA Coefficient of S **',I2,' = ')
  call PSIT(ROW1,39)
  read(*,*,err=240) ALPHA(I)
  ROW1 = ROW1 + 2
247 continue
C
call CLR
write(*,260)
260 format(1x,///,20x,'***** ALPHA COEFFICIENTS *****',//)
do 265 I = NUMCOF,1,-1
  IMIN1 = I - 1
  write(*,267) IMIN1,ALPHA(I)
267 format(26x,'ALPHA(',I2,') = ',f9.3,/)
265 continue
  ROW1 = ROW1 + 3
  write(*,269)
269 format(1x,/,5x,'Do you want to make any CHANGES to the ALPHA Coef
*ficient Values?',/,5x,'Enter "y" or "n" ==> ')
  call PSIT(ROW1,26)
  read(*,'(A)',err=240) CHG
  if ((CHG .eq. 'y') .or. (CHG .eq. 'Y')) then
    go to 240
  end if
C
C *** Enter BETA Coefficients ***
270 call CLR
  ROW1 = 10
  write(*,271)
271 format(1x,///,5x,'Enter the BETA Coefficient Values of the Charac
*teristic Equation',/,5x,'-----'
*-----',/)
do 277 I = NUMCOF,1,-1
  IMIN1 = I - 1
  write(*,280) IMIN1
280 format(1x,/,5x,'BETA Coefficient of S **',I2,' = ')
  call PSIT(ROW1,38)
  read(*,*,err=270) BETA(I)
  ROW1 = ROW1 + 2

```

```

277 continue
call CLR
write(*,290)
290 format(1x,///,20x,'***** BETA COEFFICIENTS *****',//)
do 292 I = NUMCOF,1,-1
    IMIN1 = I - 1
    write(*,294) IMIN1,BETA(I)
294 format(26x,'BETA( ',I2,',') = ',f9.3,/)

292 continue
ROW1 = ROW1 + 3
write(*,295)
295 format(1x,/,5x,'Do you want to make any CHANGES to the BETA Coeff
*icient Values?',/,5x,'Enter "y" or "n" ==> ')
call PSIT(ROW1,26)
read(*,'(A)',err=270) CHG
if ((CHG .eq. 'y') .or. (CHG .eq. 'Y')) then
    go to 270
end if
293 call CLR
CHG = 'n'
if (FLAGRT .eq. 1) then
370   write(*,371)
371   format(////,10x,'Enter ALPHA value ==> ',/,10x,'All ALPHA coef
*ficients multiplied by ALPHA')
    call PSIT(7,34)
    read(*,*,err=370) ALPHA1
372   write(*,373)
373   format(////,10x,'Enter BETA value ==> ',/,10x,'All BETA coeffic
*ients multiplied by BETA')
    call PSIT(12,33)
    read(*,*,err=372) BETA1
end if

C
C *** Enter RANGE of frequencies to examine ***
C
if (FLAGRT .ne. 1) then
    write(*,297)
297   format(1x,/,5x,'Enter the RANGE of frequencies you wish to exam
*ine',/,5x,'-----',//)
    write(*,298)
298   format(1x,/,5x,'Enter minimum frequency (WnMIN) ==> ')
    call PSIT(10,43)
    read(*,*,err=293) WNMIN
296   write(*,299)
299   format(1x,/,5x,'Enter maximum frequency (WnMAX) ==> ')
    call PSIT(13,43)

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```

      read(*,* ,err=296) WNMAX
      end if
      return
      end

C
C =====
C Subroutine MONPRT -- allows display on monitor or printer
C =====
C

      Subroutine MONPRT
      integer IOPORT,MODEL,SEL
      common/plottr/ IOPORT,MODEL

C
      call CLR
      write(*,80)
      write(*,81)
      write(*,82)
      write(*,81)
      write(*,83)
      write(*,87)
      write(*,84)
      write(*,81)
      write(*,93)

80   format(1x,///,10x,'-----'
*-----',/,10x,'|',21x,'PRINTER/OUTPUT MENU',22x,'|')
81   format(10x,'-----'
*-----')
87   format(10x,'+++++++' )
*+++++++' )
82   format(10x,'|',2x,'PRINTER NO.',2x,'|',20x,'PRINTER',19x,'|')
83   format(10x,'|',3x,'     1     ',2x,'|',4x,'Epson FX-80, All'
*,26x,'|'
*,/ ,10x,'|',3x,'     2     ',2x,'|',4x,'Epson FX-100, All'
*,25x,'|'
*,/ ,10x,'|',3x,'     3     ',2x,'|',4x,'Epson MX-100, All'
*,25x,'|'
*,/ ,10x,'|',3x,'     4     ',2x,'|',4x,'Epson RX-80, All'
*,26x,'|'
*,/ ,10x,'|',3x,'     5     ',2x,'|',4x,'Epson MX-80 & IBM Printer'
*,17x,'|'
*,/ ,10x,'|',3x,'     6     ',2x,'|',4x,'HP 7470A Graphics Plotter'
*,17x,'|'
*,/ ,10x,'|',3x,'     7     ',2x,'|',4x,'HP 7475A Graphics Plotter'
*,17x,'|'
*,/ ,10x,'|',3x,'     8     ',2x,'|',4x,'HP 758xB Series Plotters'
*,18x,'|'

```

```

*,/.,10x,'|',3x,'      9      ',2x,'|',4x,'HP 2686A Laser Jet'
*,24x,'|')
84   format(10x,'|',3x,
*'    10      ',2x,'|',4x,'Graphics Monitor (default)'
*,16x,'|'
*,/.,10x,'|',3x,'    11      ',2x,'|',4x,'HARDWARE Interface Menu'
*,19x,'|'
*,/.,10x,'|',3x,'    12      ',2x,'|',4x,'Input PLOT88 Values for IOPO
*RT and MODEL'
*,2x,'|'
*,/.,10x,'|',3x,'    99      ',2x,'|',4x,'EXIT to Main Menu',25x,'|')
93   format(1x,///,15x,'Enter integer number for selection ===> ')
call PSIT(24,56)
read(*,*) SEL
read(*,*) SEL
if (SEL .eq. 1) then
  IOPORT = 0
  MODEL = 5
else if (SEL .eq. 2) then
  IOPORT = 0
  MODEL = 15
else if (SEL .eq. 3) then
  IOPORT = 0
  MODEL = 11
else if (SEL .eq. 4) then
  IOPORT = 0
  MODEL = 1
else if (SEL .eq. 5) then
  IOPORT = 0
  MODEL = 1
else if (SEL .eq. 6) then
  IOPORT = 9600
  MODEL = 20
else if (SEL .eq. 7) then
  IOPORT = 9600
  MODEL = 30
else if (SEL .eq. 8) then
  IOPORT = 9600
  MODEL = 80
else if (SEL .eq. 9) then
  IOPORT = 9600
  MODEL = 60
else if (SEL .eq. 11) then
  call PORT
else if (SEL .eq. 12) then
  call CLR

```

```

        write(*,100)

100    format(1x,////,5x,'Input value to be used by the PLOT88 graphics
      * package',/,5x,'for IOPORT ==>',//)
            call PSIT(7,21)
            read(*,*) IOPORT
            write(*,110)

110    format(1x,///,5x,'Input value to be used by the PLOT88 graphics
      *package',/,5x,'for MODEL ==>',//)
            call PSIT(12,20)
            read(*,*) MODEL
            else
                IOPORT = 99
                MODEL = 99
            endif
            write(*,98) IOPORT,MODEL
98     format(//.10x,'PLOT88 will use these values to output graphics:'
      *,//.10x,'IOPORT = ',I4,10x,'MODEL = ',I4,///)
            PAUSE
            return
            end

C
C =====
C Subroutine PORT -- allows selection of output printer port
C =====
C
        Subroutine PORT
        integer IOPORT,MODEL,SEL
        common/plottr/ IOPORT,MODEL
C
        call CLR
        write(*,79)

79     format(1x,///,15x,'Selection of a printer in the previous menu aut
      *omatically',/,10x,'selects the most commonly associated output por
      *t, be it parallel ',/,10x,
      *'(LPT) or serial, for that particular device. If the program graph
      *ics',/,10x,
      *'are not being output correctly, use this menu to properly route t
      *he',/,10x,
      *'graphics data to the output device.',///)
            PAUSE

C
        call CLR
        write(*,80)
        write(*,81)
        write(*,82)

```

```

        write(*,81)
        write(*,83)
        write(*,87)
        write(*,84)
        write(*,81)
        write(*,93)
80      format(1x,///,10x,'-----
*-----',/,10x,'|',19x,'HARDWARE INTERFACE MENU'
*,20x,'|')
81      format(10x,'-----
*-----')
87      format(10x,'+++++',20x,'SELECT NO.',3x,'|',20x,'PORT',22x,'|')
83      format(10x,'|',3x,'    1    ',2x,'|',14x,'LPT1 Printer Port'
*,15x,'|'
*,/10x,'|',3x,'    2    ',2x,'|',14x,'LPT2 Printer Port'
*,15x,'|'
*,/10x,'|',3x,'    3    ',2x,'|',14x,'LPT3 Printer Port'
*,15x,'|'
*,/10x,'|',3x,'    4    ',2x,'|',14x,'COM1 Serial Port'
*,16x,'|'
*,/10x,'|',3x,'    5    ',2x,'|',14x,'COM2 Serial Port'
*,16x,'|')
84      format(10x,'|',3x,
*' 99  ',2x,'|',14x,'EXIT to Main Menu',15x,'|')
93      format(1x,///,15x,'Enter integer number for selection ==> ')
call PSIT(21,56)
read(*,*) SEL
if (SEL .eq. 1) then
  IOPORT = 0
else if (SEL .eq. 2) then
  IOPORT = 2
else if (SEL .eq. 3) then
  IOPORT = 3
else if (SEL .eq. 4) then
  IOPORT = 0
else if (SEL .eq. 5) then
  IOPORT = 50
else
  IOPORT = 99
endif
if ((SEL .eq. 4) .or. (SEL .eq. 5)) then
  if ((SEL .eq. 4) .or. (SEL .eq. 5)) then
C
    call CLR

```

```

        write(*,60)
        write(*,61)
        write(*,62)
        write(*,61)
        write(*,63)
        write(*,61)
        write(*,93)
60    format(1x,///,10x,'-----
*-----',/,10x,'|',16x,'BAUD (data transfer) RATE MENU'
*,16x,'|')
61    format(10x,'-----
*-----')
62    format(10x,'|',2x,'SELECT NO.',3x,'|',15x,'BAUD RATE',22x,'|')
63    format(10x,'|',3x,'     1      ',2x,'|',18x,' 300'
*,24x,'|'
*,/,10x,'|',3x,'     2      ',2x,'|',18x,'1200'
*,24x,'|'
*,/,10x,'|',3x,'     3      ',2x,'|',18x,'4800'
*,24x,'|'
*,/,10x,'|',3x,'     4      ',2x,'|',18x,'9600'
*,24x,'|')
        call PSIT(18,56)
        read(*,*) SEL
        if (SEL .eq. 1) then
            IOPORT = IOPORT + 300
        else if (SEL .eq. 2) then
            IOPORT = IOPORT + 1200
        else if (SEL .eq. 3) then
            IOPORT = IOPORT + 4800
        else
            IOPORT = IOPORT + 9600
        endif
C
        call CLR
        write(*,50)
        write(*,51)
        write(*,52)
        write(*,51)
        write(*,53)
        write(*,51)
        write(*,93)
50    format(1x,///,10x,'-----
*-----',/,10x,'|',25x,'PARITY MENU'
*,26x,'|')
51    format(10x,'-----
*-----')

```

```

52  format(10x,'|',2x,'SELECT NO.',3x,'|',17x,'PARITY',23x,'|')
53  format(10x,'|',3x,'      1      ',2x,'|',14x,' NO Parity'
*,22x,'|'
*,/,10x,'|',3x,'      2      ',2x,'|',14x,'EVEN Parity'
*,21x,'|'
*,/,10x,'|',3x,'      3      ',2x,'|',14x,'ODD Parity'
*,22x,'|')
call PSIT(17,56)
read(*,*) SEL
end if
if (SEL .eq. 3) then
    IOPORT = IOPORT + 1
else if (SEL .eq. 2) then
    IOPORT = IOPORT + 2
endif
99 return
end

C
C =====
C Subroutine SAMPLE -- demonstrates input of characteristic equation
C =====
C
Subroutine SAMPLE
C
call CLR
write(*,10)
10 format(1x,///,1x,'-----
*-----',/,5x,
*'*** This subroutine demonstrates loading a Characteristic Equatio
*n ***',/,1x,'-----
*-----',//)
write(*,20)
20 format(1x,
*'A universal third order system is represented by the characterist
*ic equation:',//,20x,'s**3 + As**2 + Bs + 1 = 0',//,1x,
*'A and B are variables representing user defined compensator param
*eters',//,10x,
*'The characteristic equation is obtained with a 1/s**3 plant',//,
*5x,'incorporating both acceleration (s**2) and velocity (s',//,
*,5x,'feedback and assigning variables A and B as the respective',//,
*,5x,'gain terms of the two compensators',//,10x,
*'To load this characteristic equation into the computer model firs
*t',//,5x,
*'select option 2 in the introductory LOAD/INSERT Menu or option 6

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```

*in the'./,5x,

*'MAIN Menu. Both options are titled "INPUT Characteristic Equation
*".',//)
PAUSE
call CLR
write(*,30)
30  format(1x,//,10x,
*'You will be asked to insert CONSTANT, ALPHA and BETA coefficients
*.',/,5x,
*'In the case of the universal third order system, the appropriate
*response',/,5x,'following each prompt is:',//,20x,
*'CONSTANT Coefficient of S ** 3 =      1',/,20x,
*'CONSTANT Coefficient of S ** 2 =      0',/,20x,
*'CONSTANT Coefficient of S ** 1 =      0',/,20x,
*'CONSTANT Coefficient of S ** 0 =      1',/,20x,
*'ALPHA Coefficient of S ** 3 =        0',/,20x,
*'ALPHA Coefficient of S ** 2 =        1',/,20x,
*'ALPHA Coefficient of S ** 1 =        0',/,20x,
*'ALPHA Coefficient of S ** 0 =        0',/,20x,
*'BETA Coefficient of S ** 3 =         0',/,20x,
*'BETA Coefficient of S ** 2 =         0',/,20x,
*'BETA Coefficient of S ** 1 =         1',/,20x,
*'BETA Coefficient of S ** 0 =         0',/,20x,////)
PAUSE
call CLR
write(*,40)
40  format(1x,//,5x,
*'When each set of responses is complete, they will be echoed back
*for',/,5x,
*'verification.',//,10x,
*'You will next be asked to enter the minimum and maximum frequenci
*es',/,5x,
*'you wish to examine. This is the natural undamped frequency range
* over',/,5x,
*'which the relative damping coefficient (zeta) will be calculated
*to',/,5x,
*'construct the constant zeta curves.',//,10x,
*'Generally, the minimum and maximum frequencies will be dictated b
*y the',/,5x,
*'desired system response. For example, we wish to have a system se
*ttling',/,5x,
*'time of less than 2 seconds. Settling time is approximated by the
* equation',/,5x,
*'4 divided by the product of relative damping coefficient and unda
*mped',/,5x,

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```

*'natural frequency. If we wish to look at a range of zeta values f
*rom .1'./,5x,
*'to 1, we can solve for the applicable min and max frequencies. In
* this'./,5x,
*'case they are 2 Hz and 20 Hz.',///)
PAUSE

      return
      end
C
C =====
C Subroutine REVCHG -- allows review or change of entered data
C =====
C
      Subroutine REVCHG (ORDER,NUMCOF,CONST,ALPHA,BETA,WNMIN,WNMAX,
*                      SEL,FLAG)
      real CONST(10),ALPHA(10),BETA(10),WNMIN,WNMAX
      integer CHG,ORDER,NUMCOF,FLAG,SEL,ROW
      call CLR
90   write(*,100)
100  format(1x,///,10x,'***** Characteristic Equation Coefficients ****
**',//)
      write(*,3) WNMIN,WNMAX,ORDER
3    format(5x,'WNMIN = ',f12.3,5x,'WNMAX = ',f12.3,5x,
*          'ORDER = ',I2,//)
      do 9 I = NUMCOF,1,-1
         J = I - 1
      write(*,4) J,CONST(I),J,ALPHA(I),J,BETA(I)
9   continue
4   format(1X,'CONST(',I2,',') = ',f10.3,5x,'ALPHA(',I2,',') = ',f10.3,5x,
*          'BETA(',I2,',') = ',f10.3)
      write(*,5)
5   format(1x,/,5x,'Do you want to make any CHANGES to the Coefficien
*t Values?',/,5x,'Enter "y" or "n" ==> ')
      ROW = 16 + NUMCOF
      call PSIT(ROW,27)
      read(*,'(A)',err=90) CHG
      if ((CHG .eq. 'y') .or. (CHG .eq. 'Y')) then
         SEL = 6
         FLAG = 1
      end if
      return
      end

```

```

C
C ****
C          CURVE SELECTION MODULE
C ****
C
C
C =====
C Subroutine CRVSEL -- allows selection of desired constant curves
C =====
C
C
Subroutine CRVSEL (CONST,ALPHA,BETA,ZETA,NUMZTA,STOP,NUMCOF,
*                      WNMIN,WNMAX,FLAG,SEL,NUMWN,WN,
*                      STOPO,ORDER,ZWN,NUMZWN,STOPZO)
real R,WNMIN,U,U1,U2,B1,B2,C1,C2,D1,D2,ZETA(10),INCZOM,
*      WNMAX,WNMIN1,CONST(10),ALPHA(10),BETA(10),A(1002),B(1002),
*      INCLOG,MAXLOG,MINLOG,WN(10),INC1,ZETA1,AOMEGA(1002),INCZWN,
*      BOMEGA(1002),ALPHA1,BETA1,ZWN(10),AZTAOM(1002),BZTAOM(1002)
integer SEL,SEL3,ORDER,NUMCOF,NUMZTA,I,M,N,K,L,ROW2,COLM,
*      START,STOP,FLAG,FRQCHG,NUMWN,TABLE,
*      STARTO,STOPO,ZTASEL,FLAGRT,NUMZWN,STOPZO,OUT
character*1 ANS
character*12 FILENAME
common A,B,AOMEGA,BOMEGA,AZTAOM,BZTAOM
common/filename/ FILENAME
logical EXIST
FILENAME = ' '
C
20    call CLR
      write(*,21)
      write(*,32)
      write(*,22)
      write(*,32)
      write(*,23)
      write(*,32)
      write(*,38)
21    format(1x,/,10x,'-----'
*-----',/,10x,'|',16x,'CURVE DATA POINT DISPLAY MENU',
*17x,'|')
22    format(10x,'|',2x,'OPTION NO.',2x,'|',15x,'OUTPUT SELECTION'
*,16x,'|')
23    format(10x,'|',2x,'     1      ',2x,'|',5x,'NO output DISPLAY or sav
*e to FILE',9x,'|'
*,/,10x,'|',2x,'     2      ',2x,'|',5x,'DISPLAY every 10th alpha/bet
*a value',7x,'|'
*,/,10x,'|',2x,'     3      ',2x,'|',5x,'DISPLAY alpha/beta values an
*d roots',7x,'|'

```

```

*,/,,10x,'|',2x,'      4      ',2x,'|',5x,'DISPLAY & FILE alpha/betas a
*nd roots',6x,'|'
*,/,,10x,'|',2x,'      5      ',2x,'|',5x,'FILE all alpha/beta values'
*,/,,10x,'|',2x,'      6      ',2x,'|',5x,'FILE all alpha/beta values a
*nd roots',6x,'|')
28   format(1x,///,15x,'Enter integer number for selection ===> ')
call PSIT(19,56)
read(*,*,err=20) OUT
call CLR
if ((OUT .lt. 4) .or. (OUT .gt. 6)) go to 30
29 write(*,101)
101 format(1x,///,10x,'What is the file name (fn) and extension (ext)
*? ',/,,10x,'Enter in form fn.ext (.ext is optional) ===> ')
call PSIT(8,56)
read(*,102) FILENAME
102 format(a12)
inquire(file=FILENAME,exist=EXIST)
if (EXIST) then
  write(*,103)
103 format(///,10x,'That file already exists.',/,10x,
*           'Do you want to overwrite? (Y/N)')
read(*,'(A1)') ANS
if((ANS .eq. 'Y') .or. (ANS .eq. 'y')) then
  open(8,file=FILENAME,status='OLD')
  rewind 8
  goto 30
else
  goto 29
end if
end if
1   open(8,file=FILENAME,status='NEW')
write(8,196) WNMIN,WNMAX
196 format(1x,///,10x,'WNMIN =',g11.4,9x,'WNMAX ='
*                  ,g11.4,/)
30   call CLR
write(*,31)
write(*,32)
write(*,33)
write(*,32)
write(*,34)
write(*,37)
write(*,35)
write(*,37)
write(*,36)
write(*,32)
write(*,38)

```



```

42  format(10x,'-----')
     *-----')
43  format(10x,'|',2x,'OPTION NO.',2x,'|',14x,'ZETA CURVE SELECTION'
     *,13x,'|')
44  format(10x,'|',2x,'    1      ',2x,'|',5x,'Select particular consta
     *nt ZETA curves',4x,'|'
     */,10x,'|',2x,'    2      ',2x,'|',5x,'ZETA = 0  curve',27x,'|'
     */,10x,'|',2x,'    3      ',2x,'|',5x,'ZETA = 0,0.5 and 1.0 curves'
     *,15x,'|'
     */,10x,'|',2x,'    4      ',2x,'|',5x,'ZETA = 0,0.25,0.5,0.75,1.0 c
     *urves',9x,'|')
45  format(10x,'|',2x,'    9      ',2x,'|',5x,'EXIT to Curve Selection
     *Menu',14x,'|')
46  format(10x,'+++++++',15x,'Enter integer number for selection ===> ')
call PSIT(19,56)
read(*,*,err=30) ZTASEL
C
C                               *** CONSTANT ZETA CURVE SELECTION ***
FRQCHG = 0
if (ZTASEL .eq. 2) then
  NUMZTA = 1
  ZETA(1) = 0.
  go to 380
else if (ZTASEL .eq. 3) then
  NUMZTA = 3
  ZETA(1) = 0.
  ZETA(2) = .5
  ZETA(3) = 1.
  go to 380
else if (ZTASEL .eq. 4) then
  NUMZTA = 5
  ZETA(1) = 0.
  ZETA(2) = .25
  ZETA(3) = .5
  ZETA(4) = .75
  ZETA(5) = 1.
  go to 380
else if (ZTASEL .eq. 9) then
  go to 30
end if
C
call CLR
write(*,331)

```

```

331      format(1x,///,10x,'This is the constant ZETA curve routine'
*     * ./,10x,'-----')
C
C      *** Enter Number of Constant ZETA Curves ***
      write(*,341)
      write(*,349)
341      format(1x,///,10x,'How many constant ZETA curves do you wish to
* plot? ',/)
349      format(10x,'Enter integer value less than or equal to 10 ==> ')
      call PSIT(14,60)
      read(*,*) NUMZTA
      call CLR
      write(*,342)
342      format(1x,///,5x,'Enter constant ZETA values in the range:  0 <=
* ZETA <= 1.0',/,5x,'-----
*-----')
      ROW2 = 6
      do 377 I = 1,NUMZTA,1
      write(*,343) I
343      format(1x,/,10x,'ZETA(',I2,',') = ')
      ROW2 = ROW2 + 3
      call PSIT(ROW2,23)
      read(*,*) ZETA(I)
377      continue
C
380      call CLR
C
      FRQCHG = 0
      MAXLOG = alog10(WNMAX)
      MINLOG = alog10(WNMIN)
      INCLOG = (MAXLOG - MINLOG)/99.
      START = -99
      STOP = 0
      DO 308 I=1,NUMZTA
          START = START + 100
          STOP = STOP + 100
          if ((START.eq.1).and.((OUT.eq.1).or.(OUT.eq.5).or.
*           (OUT.eq.6))) write (*,888)
888      format (/////////////,25x,'* * * Computing Data * * *')
          if ((OUT .ge. 2) .and. (OUT .le. 4)) then
              write(*,326) I,ZETA(I)
              format(1X,/,10x,'ZETA(',I2,',') =' ,g11.4,/)
          end if
          if ((OUT .ge. 4) .and. (OUT .le. 6)) then
              write(8,326) I,ZETA(I)
          endif

```

328

```
R = 0.
WNMIN2 = WNMIN
DO 306 L = START,STOP
    B1 = 0.
    B2 = 0.
    C1 = 0.
    C2 = 0.
    D1 = 0.
    D2 = 0.
DO 303 N=1,NUMCOF
    K = N-1
    IF (K) 302,301,302
301        U = 0.0
        U1 = -1.0
302        U2 = 2.0*ZETA(I)*U-U1
        D1 = (-1.0)**K*CONST(N)*WNMIN2**K*U1+D1
        D2 = (-1.0)**K*CONST(N)*WNMIN2**K*U+D2
        C1 = (-1.0)**K*BETA(N)*WNMIN2**K*U1+C1
        C2 = (-1.0)**K*BETA(N)*WNMIN2**K*U+C2
        B1 = (-1.0)**K*ALPHA(N)*WNMIN2**K*U1+B1
        B2 = (-1.0)**K*ALPHA(N)*WNMIN2**K*U+B2
        U1 = U
        U = U2
303        CONTINUE
C
Z = 1.0E-5
R = R+1.

C
c . . . check for division by ~ 0
    if (((ABS(B1*C2-B2*C1)) .le. 1.e-12) .and.
        (L .ne. 1)) then
        A(L) = A(L-1)
        B(L) = B(L-1)
        write (*,800) L
        if ((OUT .ge. 4) .and. (OUT .le. 6)) then
            write (8,800) L
        end if
800        format (5x,'Denominator approximately zero at point ',I3
        * ,/,5x,'This point now assigned previous point value')
            goto 802
        else
304            A(L) = (C1*D2-C2*D1)/(B1*C2-B2*C1)
            B(L) = (B2*D1-B1*D2)/(B1*C2-B2*C1)
        end if
C
c . . . check for apparent discontinuity - graphics can't handle it
```

```

        if (L .gt. 1) then
        if ((abs(A(L) - A(L-1)) .gt. 1.e6)
*
           .or. (abs(B(L) - B(L-1)) .gt. 1.e6)) then
            A(L) = A(L-1)
            B(L) = B(L-1)
            write (*,801) L
            if ((OUT .ge. 4) .and. (OUT .le. 6)) then
              write (8,801) L
            end if
            format (5x,'Apparent Discontinuity at point ',I3,
801
*
           /,5x,'This point now assigned previous point value')
            end if
            end if

C
802      if (OUT .eq. 1) goto 309
        if ((OUT .eq. 5) .or. (OUT .eq. 6)) goto 307
        if (amod(R,10.)) 307,305,307
        305      write(*,325) L,A(L),L,B(L)
        325      format(11x,'A(',I3,') = ',g11.4,9x,'B(',I3,') = ',
*
           g11.4)
        307      if (OUT .eq. 2) goto 309
        if ((OUT .ge. 4) .and. (OUT .le. 6)) then
          write(8,325) L,A(L),L,B(L)
        endif
        if (OUT .eq. 5) goto 309
        ALPHA1 = A(L)
        BETA1 = B(L)
c
c      *      call CRVOUT (OUT,L,A(L),B(L),ALPHA1,BETA1,WN,SEL3,
c      *                  MINLOG,INCLOG,INC1,B1,B2,C1,C2,D1,D2)
        call ROOTS (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,
*
           WNMAX,ALPHA1,BETA1,FLAGRT,OUT,R)

C
309      continue
        WNMN2 = 10.**(MINLOG + R*INCLOG)
306      continue
        if((OUT .ge. 2) .and. (OUT .le. 4)) then
          write(*,381)
381      format(1x,///)
          PAUSE
          call CLR
        end if

C
308  continue
C
C      *** CONSTANT OMEGA PLOTS ***
C

```

```

        else if (SEL3 .eq. 2) then
          write(*,431)
431      format(1x,///,10x,'This is the constant OMEGA curve routine'
*     ,/,10x,'-----')
C
C      *** Enter Number of Constant OMEGA Curves ***
      write(*,441)
      write(*,449)
441      format(1x,///,10x,'How many constant OMEGA curves do you wish t
*o plot? ',/)
449      format(10x,'Enter integer value less than or equal to 10 ==> ')
      call PSIT(14,60)
      read(*,*) NUMWN
      call CLR
      write(*,442)
442      format(1x,///,5x,'Enter constant OMEGA values',/,
*                 5x,'-----')
      ROW2 = 6
      do 477 I = 1,NUMWN,1
      write(*,443) I
443      format(1x,/,10x,'OMEGA(',I2,',') = ')
      ROW2 = ROW2 + 3
      call PSIT(ROW2,24)
      read(*,*) WN(I)
477    continue
C
480      call CLR
      INC1 = 1/99.
      STARTO = -99
      STOPO = 0
      DO 408 I=1,NUMWN
        STARTO = STARTO + 100
        STOPO = STOPO + 100
        if ((STARTO.eq.1).and.((OUT.eq.1).or.(OUT.eq.5).or.
*           (OUT.eq.6))) write (*,888)
        if ((OUT .ge. 2) .and. (OUT .le. 4)) then
          write(*,426) I,WN(I)
426      format(1X,/,10x,'OMEGA(',I2,',') = ',g11.4,/)
        end if
        if ((OUT .ge. 4) .and. (OUT .le. 6)) then
          write(8,426) I,WN(I)
        endif
        R = 0.
        ZETA1 = 0.

```

```

DO 406 L = STARTO,STOPO
    B1 = 0.
    B2 = 0.
    C1 = 0.
    C2 = 0.
    D1 = 0.
    D2 = 0.
DO 403 N=1,NUMCOF
    K = N-1
    IF (K) 402,401,402
401        U = 0.0
        U1 = -1.0
402        U2 = 2.0*ZETA1*U-U1
        D1 = (-1.0)**K*CONST(N)*WN(I)**K*U1+D1
        D2 = (-1.0)**K*CONST(N)*WN(I)**K*U+D2
        C1 = (-1.0)**K*BETA(N)*WN(I)**K*U1+C1
        C2 = (-1.0)**K*BETA(N)*WN(I)**K*U+C2
        B1 = (-1.0)**K*ALPHA(N)*WN(I)**K*U1+B1
        B2 = (-1.0)**K*ALPHA(N)*WN(I)**K*U+B2
        U1 = U
        U = U2
403        CONTINUE
C
        R = R+1.
c
c . . . check for division by ~ 0
        if ((ABS(B1*C2-B2*C1)) .le. 1.e-12) .and.
           (L .ne. 1)) then
            AOMEGA(L) = AOMEGA(L-1)
            BOMEGA(L) = BOMEGA(L-1)
            write (*,800) L
            if ((OUT .ge. 4) .and. (OUT .le. 6)) then
                write (8,800) L
            end if
            goto 803
        else
            AOMEGA(L) = (C1*D2-C2*D1)/(B1*C2-B2*C1)
            BOMEGA(L) = (B2*D1-B1*D2)/(B1*C2-B2*C1)
        end if
c
c . . . check for apparent discontinuity - graphics can't handle it
        if ((abs(AOMEGA(L) - AOMEGA(L-1)) .gt. 1.e6) .or.
*          (abs(BOMEGA(L) - BOMEGA(L-1)) .gt. 1.e6)) then
            AOMEGA(L) = AOMEGA(L-1)
            BOMEGA(L) = BOMEGA(L-1)

```

```

        write (*,801) L
        if ((OUT .ge. 4) .and. (OUT .le. 6)) then
            write (8,801) L
        end if
    end if

C
803      if (OUT .eq. 1) goto 409
        if ((OUT .eq. 5) .or. (OUT .eq. 6)) goto 407
        if (amod(R,10.)) 407,405,407
405      write(*,425) L,AOMEGA(L),L,BOMEGA(L)
425      format(11x,'AOMEGA(,I3,) = ',g11.4,9x,
                  'BOMEGA(,I3,) = ',g11.4)
407      if (OUT .eq. 2) goto 409
        if ((OUT .ge. 4) .and. (OUT .le. 6)) then
            write(8,425) L,AOMEGA(L),L,BOMEGA(L)
        endif
        if (OUT .eq. 5) goto 409
        ALPHA1 = AOMEGA(L)
        BETA1 = BOMEGA(L)
        call ROOTS (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,
                  WNMAX,ALPHA1,BETA1,FLAGRT,OUT,R)
*
C
409      continue
        ZETA1 = ZETA1 + INC1
406  continue
        if((OUT .ge. 2) .and. (OUT .le. 4)) then
            write(*,381)
            PAUSE
            call CLR
        end if
C
408  continue
C
C          *** CONSTANT ZETA*OMEGA PLOTS ***
C
        else if (SEL3 .eq. 3) then
            write(*,531)
531      format(1x,////,10x,'This is the constant ZETA*OMEGA curve routin
*e' ,/,10x,'-----')
C
C          *** Enter Number of Constant ZETA*OMEGA Curves ***
        write(*,541)
        write(*,549)
541      format(1x,////,10x,'How many constant ZETA*OMEGA curves do you w
*ish to plot? ./)
549      format(10x,'Enter integer value less than or equal to 10 ==> ')

```

```

call PSIT(14,60)
read(*,*) NUMZWN
call CLR
write(*,542)
542  format(1x,///,5x,'Enter constant ZETA*OMEGA values',/,
*                      5x,-----')
      ROW2 = 6
do 577 I = 1,NUMZWN
write(*,543) I
543  format(1x,/,10x,'ZETA*OMEGA( ',I2,' ) = ')
      ROW2 = ROW2 + 3
call PSIT(ROW2,29)
read(*,*) ZWN(I)
577 continue
C
580      call CLR
      MAXLOG = alog10(WNMAX)
      MINLOG = alog10(WNMIN)
      INCLOG = (MAXLOG - MINLOG)/99.
      START = -99
      STOPZO = 0
      DO 508 I=1,NUMZWN
          START = START + 100
          STOPZO = STOPZO + 100
          if ((START.eq.1).and.((OUT.eq.1).or.(OUT.eq.5).or.
*              (OUT.eq.6))) write (*,888)
          if ((OUT.ge. 2) .and. (OUT.le. 4)) then
              write(*,526) I,ZWN(I)
              format(1X,/,10x,'ZETA*OMEGA( ',I2,' ) = ',g11.4,/)
          end if
          if ((OUT .ge. 4) .and. (OUT .le. 6)) then
              write(8,526) I,ZWN(I)
          endif
          R = 0.
          WNMIN2 = WNMIN
          DO 506 L = START,STOPZO
              B1 = 0.
              B2 = 0.
              C1 = 0.
              C2 = 0.
              D1 = 0.
              D2 = 0.
              DO 503 N=1,NUMCOF
                  K = N-1
                  IF (K) 502,501,502
                  U = 0.0
501

```

```

      U1 = -1.0/WNMIN2**2.
502   U2 = -2.0*ZWN(I)*U - WNMIN2**2*U1
      D1 = CONST(N)*U1+D1
      D2 = CONST(N)*U+D2
      C1 = BETA(N)*U1+C1
      C2 = BETA(N)*U+C2
      B1 = ALPHA(N)*U1+B1
      B2 = ALPHA(N)*U+B2
      U1 = U
      U = U2
503   CONTINUE
      R = R+1.

c
c . . . check for division by ~ 0
      if ((ABS(B1*C2-B2*C1)) .le. 1.e-12) .and.
         (L .ne. 1)) then
         AZTAOM(L) = AZTAOM(L-1)
         BZTAOM(L) = BZTAOM(L-1)
         write (*,800) L
         if ((OUT .ge. 4) .and. (OUT .le. 6)) then
            write (8,800) L
         end if
         goto 804
      else
504   AZTAOM(L) = (C1*D2-C2*D1)/(B1*C2-B2*C1)
         BZTAOM(L) = (B2*D1-B1*D2)/(B1*C2-B2*C1)
      end if

c
c . . . check for apparent discontinuity - graphics can't handle it
      if ((abs(AZTAOM(L) - AZTAOM(L-1)) .gt. 1.e6) .or.
*           (abs(BZTAOM(L) - BZTAOM(L-1)) .gt. 1.e6)) then
         AZTAOM(L) = AZTAOM(L-1)
         BZTAOM(L) = BZTAOM(L-1)
         write (*,801) L
         if ((OUT .ge. 4) .and. (OUT .le. 6)) then
            write (8,801) L
         end if
      end if

c
804   if (OUT .eq. 1) goto 509
      if ((OUT .eq. 5) .or. (OUT .eq. 6)) goto 507
      if (amod(R,10.)) 507,505,507
505   write(*,525) L,AZTAOM(L),L,BZTAOM(L)
525   format(11x,'AZTAOM( ',I3,' ) = ',g11.4,9x,
*                   'BZTAOM( ',I3,' ) = 'g11.4)
507   if (OUT .eq. 2) goto 509

```

```

        if ((OUT .ge. 4) .and. (OUT .le. 6)) then
            write(8,525) L,AZTAOM(L),L,BZTAOM(L)
        endif
        if (OUT .eq. 5) goto 509
        ALPHA1 = AZTAOM(L)
        BETA1 = BZTAOM(L)
        call ROOTS (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,
*                               WNMAX,ALPHA1,BETA1,FLAGRT,OUT,R)

C
509      continue
        WNMINT2 = 10.**(MINLOG + R*INCLOG)

506      continue
        if((OUT .ge. 2) .and. (OUT .le. 4)) then
            write(*,381)
            PAUSE
            call CLR
        end if

C
508      continue
C
C          *** FREQUENCY RANGE CHANGE FOR CONSTANT ZETA PLOT ***
else if (SEL3 .eq. 4) then
C
C          *** Enter RANGE of frequencies to examine ***
C
        write(*,296) WNMINT,WNMAX
        write(*,297)
297      format(1x,//,5x,'Enter the RANGE of frequencies you wish to exam
*ine',/,5x,'-----',/),
        write(*,298)
298      format(1x,/,,5x,'Enter minimum frequency (WnMIN) ===> ')
        call PSIT(13,43)
        read(*,*) WNMINT
        write(*,299)
299      format(1x,//,5x,'Enter maximum frequency (WnMAX) ===> ')
        call PSIT(16,43)
        read(*,*) WNMAX
        write(*,296) WNMINT,WNMAX
296      format(1x,///,10x,'WNMIN =',g11.4,9x,'WNMAX =',g11.4)
        if (FILENAME .ne. ' ') then
            write(8,295) WNMINT,WNMAX
295      format(1x,///,10x,'WNMIN =',g11.4,9x,'WNMAX ='
*                           ,g11.4,/)
        endif
        FRQCHG = 1
        SEL3 = 1

```

```
write(*,381)
PAUSE
C
C           *** CALL PLOTTING ROUTINE ***
else if (SEL3 .eq. 5) then
    SEL = 7
    FLAG = 1
else
    continue
end if
C
C     Recompute Alpha & Beta points in constant zeta routine when
c      frequency range is changed
if(FRQCHG .eq. 1) go to 330
c
c      if(SEL3 .eq. 5) go to 399
c
c . . . If EXIT not selected, redisplay curve select menu
if(SEL3 .ne. 9) go to 30
c
399  if (FILENAME .ne. ' ') then
      close(8,STATUS='KEEP')
      endif
c
      return
end
```

```

C
C **** **** **** **** **** **** **** **** **** **** **** **** ****
C          ROOT FINDING MODULE
C **** **** **** **** **** **** **** **** **** **** **** ****
C
C
C =====
C Subroutine ROOTFD -- calculates the roots of the entered C. E.
C =====
C
C
C Subroutine ROOTS (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,WNMAX,
*                  ALPHA1,BETA1,FLAGRT,OUT,R)
    real CONST(10),ALPHA(10),BETA(10),COEF(13),A,ALPHA1,BETA1,R
    real*8 B,C,P,Q,DENOM,REAL1,IMAG1,REAL2,IMAG2,IMAGSQ,
*      REALNO,IMAGNO
    integer ORDER,I,NUMCOF,IMIN1,FLAG,FLAGRT,OUT
    character*1 CHG
    character*12 FILENAME
    common/filename/ FILENAME
    data FLAG /0/
C
C
C     if (FLAGRT .eq. 1) then
        call CHAREQ (ORDER,CONST,ALPHA,BETA,NUMCOF,WNMIN,WNMAX,
*                  FLAGRT,ALPHA1,BETA1)
    end if
C
C     call NORMAL(ORDER,NUMCOF,CONST,ALPHA,BETA,COEF,ALPHA1,BETA1,
*                  FLAGRT)
        call ROOTS2(ORDER,COEF,FLAG,P,Q,OUT,R)
    return
    end
C
C =====
C Subroutine ROOTS2 -- Reduce polynomial using Bairstow's method
C =====
C
C Subroutine ROOTS2(ORDER,COEF,FLAG,P,Q,OUT,R)
    dimension F(13),G(13)
    real EPSILON,DELTAP,DELTAQ,COEF(13),R,REDUC,PREVDP,
*      PREVDQ
    real*8 DENOM,P,Q,REAL1,IMAG1,REAL2,IMAG2,F,G
    integer J,ORDER,ORD,ORD3,N,ITERAT,MAXIT,FLAG,ORD1,OUT
    character*12 FILENAME
    logical PDIFF,QDIFF,PQCHG
    common/filename/ FILENAME
    EPSILON = .0001

```

```

MAXIT = 500
ORD = ORDER
ORD3 = ORDER + 3
ITERAT = 1
FLAG = 0
P = .1
Q = .1
F(1) = 0.
F(2) = 0.
G(1) = 0.
G(2) = 0.
DELTAP = 0.
DELTAQ = 0.

C
C . . . Check for roots at origin
C
      I = 0
      if (COEF(ORD3) .eq. 0.) then
108     I = I + 1
      ORD3 = ORD3 - 1
      ORD = ORD - 1
      if ((COEF(ORD3) .eq. 0.) goto 108
      if ( ( ( OUT .eq. 3 ) .or. ( OUT .eq. 4 ) ) .and.
* ( amod(R,10.) .eq. 0. ) then
        write (*,107) I
        write (8,*) ''
        write (8,107) I
107     format(10x,I1,' root(s) at the origin')
        end if
      end if
C
      if (ORDER .eq. 1) then
        REAL1 = -COEF(4)
        IMAG1 = 0.
        if ( ( ( OUT .eq. 3 ) .or. ( OUT .eq. 4 ) ) .and.
* ( amod(R,10.) .eq. 0. ) then
          write (*,100) REAL1, dabs(IMAG1)
100     format(1x,/,10x,'Only Root = ',5x,g11.4,' +      j',g11.4)
        end if
        if ((OUT .eq. 4) .or. (OUT .eq. 6)) then
          write (8,100) REAL1, dabs(IMAG1)
        endif
        FLAG = 1
C
      else if (ORDER .eq. 2) then
        P = COEF(4)

```

```

Q = COEF(5)
call ROOTS1(P,Q,REAL1,IMAG1,REAL2,IMAG2)
if (((OUT .eq. 3) .or. (OUT .eq. 4)) .and. (amod(R,10.) .eq. 0.))
*) then
    write (*,105) REAL1, dabs(IMAG1)
    write (*,106) REAL2, dabs(IMAG1)
    write (*,*) ' '
105   format(10x,'First Root = ',5x,g9.3,' +      j',g9.3)
106   format(10x,'Second Root = ',5x,g9.3,' -      j',g9.3)
end if
if ((OUT .eq. 4) .or. (OUT .eq. 6)) then
    write (8,105) REAL1, dabs(IMAG1)
    write (8,106) REAL2, dabs(IMAG1)
    write (8,*) ' '
endif
FLAG = 1
C
    end if
C
C . . . If all roots computed or max iterations exceeded - finished
C
10   if ((FLAG .eq. 1) .or. (ITERAT .gt. MAXIT)) go to 99
C
110  do 110 J = 3,ORD3
        F(J) = COEF(J) - P*F(J-1) - Q*F(J-2)
        G(J) = F(J) - P*G(J-1) - Q*G(J-2)
110  continue
        DENOM = G(ORD+1)**2 - (G(ORD+2)-F(ORD+2))*G(ORD)
C
        if (DENOM .ne. 0.) then
            PREVDP = DELTAP
            PREVDQ = DELTAQ
            DELTAP = (F(ORD+2)*G(ORD+1) - F(ORD+3)*G(ORD))*REDUC/DENOM
            DELTAQ = (G(ORD+1)*F(ORD+3) - (G(ORD+2)-F(ORD+2))*
*                  F(ORD+2))*REDUC/DENOM
            P = P + DELTAP
            Q = Q + DELTAQ
C
            if ((abs(P) .gt. EPSILON) .and. (abs(Q) .gt. EPSILON)) then
                PQCHG = (abs(DELTAP/P) + abs(DELTAQ/Q)) .lt. EPSILON
            else if ((abs(P) .lt. EPSILON) .and. (abs(Q) .gt. EPSILON)) then
                PQCHG = (abs(DELTAP) + abs(DELTAQ/Q)) .lt. EPSILON
            else if ((abs(P) .gt. EPSILON) .and. (abs(Q) .lt. EPSILON)) then
                PQCHG = (abs(DELTAP/P) + abs(DELTAQ)) .lt. EPSILON
            else
                PQCHG = ((abs(DELTAP) .lt. EPSILON) .and.

```

```

*          (abs(DELTAQ) .lt. EPSLON))
end if
if (PQCHG) then
    call ROOTS1(P,Q,REAL1,IMAG1,REAL2,IMAG2)
    ORD1 = ORD - 1
    if (((OUT .eq. 3) .or. (OUT .eq. 4)) .and. (amod(R,10.) .eq.
* 0.)) then
        write (*,150) ORD,REAL1,dabs(IMAG1),ORD1,REAL2,dabs(IMAG2)
150      format(1x,'Root(',I2,') = ',g11.4,' + j',g11.4,
*           5x,'Root(',I2,') = ',g11.4,' - j',g11.4)
    end if
    if ((OUT .eq. 4) .or. (OUT .eq. 6)) then
        write (8,150) ORD,REAL1,dabs(IMAG1),ORD1,REAL2,dabs(IMAG2)
    endif
    ORD = ORD - 2
C
C . . . Check order of reduced polynomial
    if (ORD .eq. 0) then
        FLAG = 1
    else if (ORD .eq. 1) then
        REAL1 = -F(ORD+3)/F(ORD+2)
        IMAG1 = 0.
        if (((OUT .eq. 3) .or. (OUT .eq. 4)) .and. (amod(R,10.) .eq.
* 0.)) then
            write (*,160) ORD,REAL1,IMAG1
160      format(1x,'Root(',I2,') = ',g11.4,' + j',g11.4,/)
        end if
        if ((OUT .eq. 4) .or. (OUT .eq. 6)) then
            write (8,160) ORD,REAL1,IMAG1
        endif
        FLAG = 1
    else
        ORD3 = ORD + 3
        do 180 J = 3,ORD3
            COEF(J) = F(J)
            ITERAT = 1
180      continue
    end if
C
    else
        ITERAT = ITERAT + 1
    end if
C
    else
        P = P + 1
        Q = Q + 1

```

```

        ITERAT = 1
    end if
C
    PDIFF = (abs(PREVDP) + abs(DELTAP)) .ne. abs(PREVDP + DELTAP)
    QDIFF = (abs(PREVDQ) + abs(DELTAQ)) .ne. abs(PREVDQ + DELTAQ)
    if ((PDIFF .and. (Q .lt. .01)) .or. (QDIFF .and. (P .lt. .01)))
*     .or. (PDIFF .and. QDIFF)) then
        REDUC = REDUC/2.
    end if
    if (FLAG .ne. 1) go to 10
99  return
    end

C
C =====
C Subroutine ROOTS1 -- Finds roots of second order polynomial
C =====
C
Subroutine ROOTS1(B,C,REAL1,IMAG1,REAL2,IMAG2)
real*8 B,C,REAL1,IMAG1,REAL2,IMAG2,REALNO,IMAGNO,IMAGSQ
C
    REALNO = -B/2.
    IMAGNO = B**2 - 4*C
    if (IMAGNO .ge. 0.) then
        IMAGSQ = dsqrt(IMAGNO)/2.
        REAL1 = REALNO + IMAGSQ
        IMAG1 = 0.
        REAL2 = REALNO - IMAGSQ
        IMAG2 = 0.
    else
        IMAGSQ = dsqrt(-IMAGNO)/2.
        REAL1 = REALNO
        IMAG1 = IMAGSQ
        REAL2 = REALNO
        IMAG2 = -IMAGSQ
    end if
C
    return
    end

C
C =====
C Subroutine NORMAL -- Adds CONST, ALPHA & BETA terms and normalizes
C =====
C
Subroutine NORMAL(ORDER,NUMCOF,CONST,ALPHA,BETA,COEF,ALPHA1,BETA1,
*                  FLAGRT)
real CONST(10),ALPHA(10),BETA(10),COEF(10),ACOEF,BCOEF,CCOEF,

```

```

*      ALPHA1,BETA1
integer J,ORDER,NUMCOF,N,M,FLAGRT
C
N = 3
M = ORDER + 3
do 10 J = NUMCOF,1,-1
    COEF(N) = CONST(J) + ALPHA(J)*ALPHA1 + BETA(J)*BETA1
    N = N + 1
10  continue
if (COEF(NUMCOF) .ne. 1.) then
    do 20 J = 4,M
        COEF(J) = COEF(J)/COEF(3)
20  continue
COEF(3) = 1.
end if
if (FLAGRT .eq. 1) then
call CLR
I = NUMCOF + 1
do 25 J = 3,M
    I = I - 1
    write (*,30) I,COEF(J)
30  format(15x,'COEF(',I2,') = ',g9.3,/)

25  continue
end if
return
end

```

```

C
C **** PLOTTING MODULE ****
C
C
C =====
C Subroutine RUNPRO -- executes the parameter plane program
C =====
C
C
Subroutine RUNPRO (NUMZTA,STOP,ZETA,CURV,NUMWN,WN,STOPO,
* ZWN,NUMZWN,STOPZO)
  real ATEMP(102),BTEMP(102),ZETA(10),A,B,AOMEGA,BOMEGA,
* XMIN,XMAX,YMIN,YMAX,FACT,XCEN,YCEN,WN(10),ZWN(10),
* EXPAMN,EXPAMX,EXPBMN,EXPBMX,AZTAOM,BZTAOM,
* EXPALP(1002),EXPBET(1002),STITLE,CRVTYP,
* AZFST,AZDLT,BZFST,BZDLT,AOFST,AODLT,BOFST,BODLT,
* AZOFST,AZODLT,BZOFST,BZODLT
  integer I,J,IOPORT,MODEL,NUMZTA,STOP,FRSTZ,DELTZ,INTRVL,CURV,
* DELT1,DELT2,NUMWN,L,K,STOPO,FRSTW,DELTW,EXPAND,INTSRT,
* INTSTP,NC,NUMZWN,STOPZO,SEL,SYMBL
  dimension A(1002),B(1002),AOMEGA(1002),BOMEGA(1002),AZTAOM(1002),
* BZTAOM(1002)
  character*1 CHG,NMCHAR(30)
  character*30 TITLE
  common A,B,AOMEGA,BOMEGA,AZTAOM,BZTAOM
  common/plottr/ IOPORT,MODEL
  common/box/ EXPAND,SYMBL
  common/factr/ FACT
c  common/symb/ SYMBL
  equivalence (NMCHAR(1),TITLE)
C
FACT = 0.9
EXPAND = 9
SYMBL = 14
C
78  call CLR
write(*,80)
write(*,81)
write(*,82)
write(*,81)
write(*,83)
write(*,81)
write(*,93)
80  format(1x,////////,10x,'-----'
*-----',/,10x,'|',24x,'PLOTTING MENU',25x,'|')

```

```

81   format(10x,'-----')
     *-----')
82   format(10x,'|',2x,'OPTION NO.',2x,'|',20x,'OPTION',21x,'|')
83   format(10x,'|',2x,'    1    ',2x,'|',5x,
     *'TITLE output graph and PLOT data',10x,'|'
     *,/,10x,'|',2x,'    2    ',2x,'|',5x,
     *'PLOT data (no title)',22x,'|'
     *,/,10x,'|',2x,'    3    ',2x,'|',5x,
     *'SIZE output graph',25x,'|'
     *,/,10x,'|',2x,'    4    ',2x,'|',5x,
     *'SYMBOL to be plotted at each data point',3x,'|'
     *,/,10x,'|',2x,'    9    ',2x,'|',5x,'EXIT to Main Menu',25x,'|')
93   format(1x,///,15x,'Enter integer number for selection ===> ')
call PSIT(23,56)
read(*,*,err=78) SEL
if (SEL .eq. 1) then
  goto 4
else if (SEL .eq. 2) then
  goto 9
else if (SEL .eq. 3) then
  goto 7
else if (SEL .eq. 4) then
  goto 5
else if (SEL .eq. 9) then
  goto 399
else
  goto 78
end if

C
C. . . Adjust size of output plot
7   call CLR
write(*,15)
15  format(////,10x,'Output plots are currently sized to fill the con
*sole screen.',//,
*      10x,'Would you like to adjust the plot size?',/,10x,
*      'Enter "y" or "n" ==> ')
call PSIT(10,31)
read(*,'(A)',err=4) CHG
if ((CHG .eq. 'n') .or. (CHG .eq. 'N')) then
  go to 78
end if
write(*,16)
16  format(///,10x,'A default plot factor size of 0.9 is used to fill
*the console screen.',/,10x,
*'This plot size will be halved by entering a value of 0.45.',/,
*10x,'It will be doubled with a factor entry of 1.8.',/,10x,

```

```

*'Enter factor size ==> ')
call PSIT(18,32)
read(*,*) FACT
goto 78
C
C. . . Select symbol to be plotted at each data point
5   call CLR
write(*,17)
17   format(/////,10x,'Type in an INTEGER number from 0 through 13 to p
*lace a',/,
* 10x,'symbol at each calculated data point. There are 100 data poi
*nts',/,
* 10x,'for each curve. Examples of symbols with associated numbers:
*',/,
* 15x,'2   Triangle',/,
* 15x,'3   +',/,
* 15x,'4   X',/,
* 15x,'8   Z',/,
* 15x,'9   Y',/,
* 15x,'11  *',/,
* 15x,'13  Vertical Line',///
* 10x,'Enter INTEGER number (0 - 13) ==> ')
call PSIT(20,45)
read(*,*,err=78) SYMBL
      go to 78
C
C. . . Enter TITLE of graph
4   call CLR
write(*,6)
6   format(/////,10x,'Enter plot title ==> ',/,/
*10x,'(30 characters max)')
call PSIT(7,31)
read(*,8) TITLE
8   format(A30)
      do 11 I = 30,1,-1
          if (NMCHAR(I) .ne. ' ') go to 13
11   continue
13   NC = I
      STITLE = 4.3 - .12*NC
C
9   call CLR
INTRVL = 0
SEL = 3
CURV = 0
call PLOTS (0,IOPORT,MODEL)
call NEWPEN (1)

```

```

C
C ..... Calculate Constant ZETA Plot
C
    if (NUMZTA .ge. 1) then
        CRVTYP = .1
        write (*,119)
119     format(///,25x,'CONSTANT ZETA CURVES')
        call PLTCRV (STOP,A,B,NUMZTA,CRVTYP,ZETA,
*                      TITLE,STITLE,NC,AZFST,AZDLT,BZFST,BZDLT)
        call PLOT (0.0,0.0,-999)
    end if

C
C ..... Calculate Constant OMEGA Plot
C
    if (NUMWN .ge. 1) then
        call CLR
        CRVTYP = -.1
        write (*,219)
219     format(///,25x,'CONSTANT OMEGA CURVES')
        call PLTCRV (STOPO,AOMEGA,BOMEGA,NUMWN,CRVTYP,WN,
*                      TITLE,STITLE,NC,AOFST,AODLT,BOFST,BODLT)
        call PLOT (0.0,0.0,-999)
    end if

C
C ..... Calculate Constant ZETA*OMEGA Plot
C
    if (NUMZWN .ge. 1) then
        call CLR
        CRVTYP = -.2
        write (*,319)
319     format(///,25x,'CONSTANT ZETA*OMEGA CURVES')
        call PLTCRV (STOPZO,AZTAOM,BZTAOM,NUMZWN,CRVTYP,ZWN,
*                      TITLE,STITLE,NC,AZOFST,AZODLT,BZOFST,BZODLT)
        call PLOT (0.0,0.0,-999)
    end if

C
C ... Calculate Zeta & Omega Plot
C
    if ((NUMZTA .ge. 1) .and. (NUMWN .ge. 1)) then
        call CLR
        ATEMP(101) = AZFST
        ATEMP(102) = AZDLT
        BTEMP(101) = BZFST
        BTEMP(102) = BZDLT
        write (*,492)
492     format(///,25x,'CONSTANT COMBINED CURVES')

```

```

        write (*,493) ATEMP(101),ATEMP(102)
493  format (///,5x,'X Axis Min Value = ',g11.4,5x,'X Axis DELTA = ',
*           g11.4,//)
        write (*,494) BTEMP(101),BTEMP(102)
494  format (5x,'Y Axis Min Value = ',g11.3,5x,'Y Axis DELTA = ',g11.4,
*           ////)
        write (*,495)
495  format (25x,'*** Calculating Data ***',////)

C
        INTRVL = 0
        call FACTOR (FACT)
        call ASPECT (1.2)
        call STAXIS (.13,.20,.15,0.1,2)
        call SYMBOL (STITLE,6.0,.25,TITLE,0.,NC)
        call AXIS (.8,.8,'Alpha',-5,-7.0,0.,AZFST,AZDLT)
        call AXIS (.8,.8,'Beta',4,-5.0,90.,BFST,BZDLT)

C
C . . . Draw dashed lines at axis increments and surrounding box
        call GRID

C
        do 470 I = 1,NUMWN
          do 480 J = 1,100
            ATEMP(J) = AOMEGA(J + INTRVL)
            BTEMP(J) = BOMEGA(J + INTRVL)
480      continue
            call CURVE (ATEMP,BTEMP,100,-.1)
            call WHERE (X,Y,FACT)
            call NUMBER (X,Y,0.15,WN(I),0.,2)
            INTRVL = INTRVL + 100
470      continue
C
        INTRVL = 0
        do 440 I = 1,NUMZTA
          do 450 J = 1,100
            ATEMP(J) = A(J + INTRVL)
            BTEMP(J) = B(J + INTRVL)
450      continue
            call CURVE (ATEMP,BTEMP,100,.1)
            call WHERE (X,Y,FACT)
            call NUMBER (X,Y,0.15,ZETA(I),0.,2)
            INTRVL = INTRVL + 100
440      continue
C
        if (NUMZWN .ge. 1) then
          INTRVL = 0
          do 540 I = 1,NUMZWN

```

```

do 550 J = 1,100
    ATEMP(J) = AZTAOM(J + INTRVL)
    BTEMP(J) = BZTAOM(J + INTRVL)
550  continue
    call CURVE (ATEMP,BTEMP,100,-.2)
    call WHERE (X,Y,FACT)
    call NUMBER (X,Y,0.15,ZWN(I),0.,2)
    INTRVL = INTRVL + 100
540  continue
    end if
    end if
    call PLOT (0.0,0.0,999)

C
C . . . Expand plot about a selected area or point
C
30   call CLR
    write(*,31)
    write(*,32)
    write(*,33)
    write(*,32)
    write(*,34)
    write(*,36)
    write(*,35)
    write(*,32)
    write(*,37)

31   format(1x,/,10x,'-----'
*-----',/,10x,'|',19x,'EXPAND PLOT MENU',27x,'|')
32   format(10x,'|-----'
*-----|')

33   format(10x,'|',2x,'OPTION NO.',2x,'|',14x,'EXPANSION SELECTION'
*,14x,'|')

34   format(10x,'|',2x,'     1      ',2x,'|',5x,'Expand area defined by a
*xes values',8x,'|'
*,/,10x,'|',2x,'     2      ',2x,'|',5x,'Expand around a selected poi
*nt',12x,'|')

35   format(10x,'|',2x,'     9      ',2x,'|',5x,'EXIT plotting routine'
*,21x,'|')

36   format(10x,'|+++++++',15x,'|+++++++',15x,'|+++++++',15x,'|+++++++',15x,'|')

37   format(1x,/,15x,'Enter integer number for selection ==> ')
    call PSIT(17,56)
    read(*,*,err=30) EXPAND

C
294  if (EXPAND .eq. 2) then
C

```

```

C . . . Expand plot around selected point
C
call CLR
write(*,295)
295 format(1x,//,5x,'Enter the POINT about which you wish to expand',
*//,5x,'-----',/,5x,'(This
*point must be entered in # of divisions on alpha & beta',/,5x,'axe
*s. An expansion about the center of the diagram would ',/,5x,'requ
*ire an entry of 3.5 for the alpha axis and 2.5 for the ',/,5x,'bet
*a axis.)',//)
write(*,297)
297 format(1x,//,5x,'Enter CENTER value for ALPHA axis (range is 0 to
*7) ===> ')
call PSIT(14,63)
read(*,*) XCEN
write(*,298)
298 format(1x,//,5x,'Enter CENTER value for BETA axis (range is 0 to 5
*) ===> ')
call PSIT(17,62)
read(*,*) YCEN
write(*,300)
300 format(1x,//,5x,'Enter value for FACTOR (enlargement) ===> ')
call PSIT(20,50)
read(*,*) FACT

c
c Compute axis scaling values
c
XCEN = XCEN * FACT
YCEN = YCEN * FACT
c
XMIN = XCEN - 3.5
XMAX = XCEN + 3.5
YMIN = YCEN - 2.5
YMAX = YCEN + 2.5
c
if (NUMZTA .eq. 0) then
  ATEMP(101) = AOFST
  ATEMP(102) = AODLT
  BTEMP(101) = BOFST
  BTEMP(102) = BODLT
else
  ATEMP(101) = AZFST
  ATEMP(102) = AZDLT
  BTEMP(101) = BZFST
  BTEMP(102) = BZDLT
end if

```

```

call CLR
write (*,392) ATEMP(101),ATEMP(102)
392 format (/////,5x,'X Axis Min Value = ',g11.4,5x,'X Axis DELTA = ',
*           g11.4,//)
write (*,393) BTEMP(101),BTEMP(102)
393 format (5x,'Y Axis Min Value = ',g11.3,5x,'Y Axis DELTA = ',g11.4,
*           ////)

C
call PLOTS (0,IOPORT,MODEL)
call WINDOW (XMIN,YMIN,XMAX,YMAX)
call FACTOR (FACT)
call ASPECT (1.2)
call STAXIS (.13,.20..15,0.1,2)
call SYMBOL (STITLE,6.0,.25,TITLE,0.,NC)
call AXIS (.8,.8,'Alpha',-5,-7.0,0.,ATEMP(101),ATEMP(102))
call AXIS (.8,.8,'Beta',4,-5.0,90.,BTEMP(101),BTEMP(102))
INTRVL = 0
write (*,331)
331 format (///,25x,'*** Calculating Data ***',//)

C
C . . . Draw dashed lines at axis increments and surrounding box
call GRID

C
do 340 I = 1,NUMZTA
    do 350 J = 1,100
        ATEMP(J) = A(J + INTRVL)
        BTEMP(J) = B(J + INTRVL)
350 continue
    call CURVE (ATEMP,BTEMP,100,.1)
    call WHERE (X,Y,FACT)
    call NUMBER (X,Y,0.15,ZETA(I),0.,2)
    if ((SYMBL .le. 13) .and. (SYMBL .ge. 0)) then
        call LINE (ATEMP,BTEMP,100,1,-1,SYMBL)
    end if
    INTRVL = INTRVL + 100
340 continue

C
INTRVL = 0
do 370 I = 1,NUMWN
    do 380 J = 1,100
        ATEMP(J) = AOMEGA(J + INTRVL)
        BTEMP(J) = BOMEGA(J + INTRVL)
380 continue
    call CURVE (ATEMP,BTEMP,100,-.1)
    call WHERE (X,Y,FACT)
    call NUMBER (X,Y,0.15,WN(I),0.,2)

```

```

        if ((SYMBL .le. 13) .and. (SYMBL .ge. 0)) then
            call LINE (ATEMP,BTEMP,100,1,-1,SYMBL)
        end if
381     continue
        INTRVL = INTRVL + 100
370     continue
        call PLOT (0.0,0.0,999)
        FACT = 0.9

C
C
C . . . Enter RANGE of ALPHA & BETA values to examine
C
        else if (EXPAND .eq. 1) then
            call CLR
700        write(*,701)
701        format(///,10x,'Enter Minimum ALPHA axis value ==> ')
            call PSIT(6,48)
            read(*,* ,err=700) EXPAMN
702        write(*,703)
703        format(/,10x,'Enter Maximum ALPHA axis value ==> ')
            call PSIT(8,48)
            read(*,* ,err=702) EXPAMX
704        write(*,705)
705        format(/,10x,'Enter Minimum BETA axis value ==> ')
            call PSIT(10,47)
            read(*,* ,err=700) EXPBMN
706        write(*,707)
707        format(/,10x,'Enter Maximum BETA axis value ==> ')
            call PSIT(12,47)
            read(*,* ,err=702) EXPBMX

C
C . . . Calculate Constant ZETA Plot
        if (NUMZTA .ge. 1) then
            J = 0
            do 710 I = 1,STOP
                if((A(I) .ge. EXPAMN) .and. (A(I) .le. EXPAMX)) then
                    if((B(I) .ge. EXPBMN) .and. (B(I) .le. EXPBMX)) then
                        J = J + 1
                        EXPALP(J) = A(I)
                        EXPBET(J) = B(I)
                    end if
                end if
710            continue
                FRSTZ = J + 1
                DELTZ = J + 2

```

C

```

        call SCALE (EXPALP,7.0,J,1)
        call SCALE (EXPBET,5.0,J,1)

C
        write (*,711)
711     format(////////,30x,'WINDOW EXPANSION')
        write (*,712) EXPALP(FRSTZ),EXPALP(DELTZ)
712     format (/////,5x,'X Axis Min Value = ',g11.4,5x,'X Axis DELTA = ',
*           g11.4,//)
        write (*,714) EXPBET(FRSTZ),EXPBET(DELTZ)
714     format (5x,'Y Axis Min Value = ',g11.3,5x,'Y Axis DELTA = ',g11.4,
*           ////)
        write (*,716)
716     format (///,25x,'*** Calculating Data ***',//)

C
        call PLOTS (0,IOPORT,MODEL)
        call FACTOR (FACT)
        call NEWPEN (1)
        call ASPECT (1.2)
        call STAXIS (.13,.20,.15,0.1,2)
        call SYMBOL (STITLE,6.0,.25,TITLE,0.,NC)
        call AXIS (.8,.8,'Alpha',-5,-7.0,0.,EXPALP(FRSTZ),EXPALP(DELTZ))
        call AXIS (.8,.8,'Beta',4,-5.0,90.,EXPBET(FRSTZ),EXPBET(DELTZ))

C
C . . . Draw dashed lines at axis increments and surrounding box
        call GRID

C
        INTSRT = 1
        INTSTP = 100
        do 720 K = 1,NUMZTA
        J = 0
        J1 = 0
        do 730 I = INTSRT,INTSTP
            if((A(I) .ge. EXPAMN) .and. (A(I) .le. EXPAMX)) then
                if((B(I) .ge. EXPBMN) .and. (B(I) .le. EXPBMX)) then
                    J = J + 1
                    ATEMP(J) = A(I)
                    BTEMP(J) = B(I)
                end if
            end if
        continue
730     ATEMP(J+1) = EXPALP(FRSTZ)
        ATEMP(J+2) = EXPALP(DELTZ)
        BTEMP(J+1) = EXPBET(FRSTZ)
        BTEMP(J+2) = EXPBET(DELTZ)
        call CURVE (ATEMP,BTEMP,J,.1)
        if ((SYMBL .le. 13) .and. (SYMBL .ge. 0)) then

```

```

        call LINE (ATEMP,BTEMP,J,1,-1,SYMBL)
end if
J1 = J-1
call WHERE(X,Y,FACT)
call NUMBER (X,Y,0.15,ZETA(K),0.,2)
INTSRT = INTSRT + 100
INTSTP = INTSTP + 100
720    continue
end if

C
C . . . Constant Wn curves
C
if (NUMWN .ge. 1) then
if (NUMZTA .ge. 1) go to 819
J = 0
do 810 I = 1,STOPO
  if((AOMEGA(I) .ge. EXPAMN) .and. (AOMEGA(I) .le. EXPAMX))
*   then
    if((BOMEGA(I) .ge. EXPBMN) .and. (BOMEGA(I) .le. EXPBMX))
*   then
      J = J + 1
      EXPALP(J) = AOMEGA(I)
      EXPBET(J) = BOMEGA(I)
    end if
  end if
810    continue
FRSTZ = J + 1
DELTZ = J + 2

C
call SCALE (EXPALP,7.0,J,1)
call SCALE (EXPBET,5.0,J,1)

C
write (*,811)
811  format(////////,30x,'WINDOW EXPANSION')
write (*,812) EXPALP(FRSTZ),EXPALP(DELTZ)
812  format (/////,5x,'X Axis Min Value = ',g11.4,5x,'X Axis DELTA = ',
*           g11.4,/)
write (*,814) EXPBET(FRSTZ),EXPBET(DELTZ)
814  format (5x,'Y Axis Min Value = ',g11.3,5x,'Y Axis DELTA = ',g11.4,
*           //++)
write (*,816)
816  format (///,25x,'*** Calculating Data ***',//)

C
call PLOTS (0,IOPORT,MODEL)
call FACTOR (0.9)
call NEWPEN (1)

```

```

call ASPECT (1.2)
call STAXIS (.13,.20,.15,0.1,2)
call SYMBOL (STITLE,6.0,.25,TITLE,0.,NC)
call AXIS (.8,.8,'Alpha',-5,-7.0,0.,EXPALP(FRSTZ),EXPALP(DELTZ))
call AXIS (.8,.8,'Beta',4,-5.0,90.,EXPBET(FRSTZ),EXPBET(DELTZ))

C
C . . . Draw dashed lines at axis increments and surrounding box
call GRID
C

819   INTSRT = 1
      INTSTP = 100
      do 820 K = 1,NUMWN
          J = 0
          J1 = 0
          do 830 I = INTSRT,INTSTP
              if((AOMEGA(I) .ge. EXPAMN) .and. (AOMEGA(I) .le. EXPAMX))
*            then
*                if((BOMEGA(I) .ge. EXPBMN) .and. (BOMEGA(I) .le. EXPBMX))
*                then
                    J = J + 1
                    ATEMP(J) = AOMEGA(I)
                    BTEMP(J) = BOMEGA(I)
                    end if
                end if
            continue
          ATEMP(J+1) = EXPALP(FRSTZ)
          ATEMP(J+2) = EXPALP(DELTZ)
          BTEMP(J+1) = EXPBET(FRSTZ)
          BTEMP(J+2) = EXPBET(DELTZ)
          call CURVE (ATEMP,BTEMP,J,-.1)
          if ((SYMBL .le. 13) .and. (SYMBL .ge. 0)) then
              call LINE (ATEMP,BTEMP,J,1,-1,SYMBL)
          end if
          call WHERE(X,Y,FACT)
          call NUMBER (X,Y,0.15,WN(K),0.,2)
          J1 = J-1
          INTSRT = INTSRT + 100
          INTSTP = INTSTP + 100
820   continue
      end if
      call PLOT (0.0,0.0,999)
  else
      go to 399
  end if

C
C

```

```

call CLR
write(*,239)
239 format(1x,////////,9x,'Do you want to make another WINDOW selection
*?'//,9x,'Enter "y" or "n" ==> ')
call PSIT(11,31)
read(*,'(A)',err=399) CHG
if ((CHG .eq. 'y') .or. (CHG .eq. 'Y')) then
    go to 30
end if
399 call CLR
write(*,238)

238 format(1x,////////,9x,'Do you want to SAVE your constant CURVE sele
*ctions? '//,9x,'Enter "y" or "n" ==> ')
call PSIT(11,31)
read(*,'(A)',err=399) CHG
if ((CHG .eq. 'n') .or. (CHG .eq. 'N')) then
    NUMZTA = 0
    NUMWN = 0
    NUMZWN = 0
end if
return
end

C
C =====
C Subroutine GRID -- draws dashed lines at axis increments
C =====
C
Subroutine GRID
integer EXPAND,SYMBL
common/box/ EXPAND,SYMBL
C
if (EXPAND .eq. 2) then
    call PLOT (0.8,0.8,-3)
else
    call PLOT (0.8,0.8,-3)
endif
call PLOT (0.0,5.0,3)
call PLOT (7.0,5.0,2)
call PLOT (7.0,0.0,2)
call STDASH (.01,.10)
call PLOTD (1.0,0.0,3)
call PLOTD (1.0,5.0,2)
call PLOTD (2.0,5.0,3)
call PLOTD (2.0,0.0,2)
call PLOTD (3.0,0.0,3)

```

```

call PLOTD (3.0,5.0,2)
call PLOTD (4.0,5.0,3)
call PLOTD (4.0,0.0,2)
call PLOTD (5.0,0.0,3)
call PLOTD (5.0,5.0,2)
call PLOTD (6.0,5.0,3)
call PLOTD (6.0,0.0,2)
call PLOTD (7.0,1.0,3)
call PLOTD (0.0,1.0,2)
call PLOTD (0.0,2.0,3)
call PLOTD (7.0,2.0,2)
call PLOTD (7.0,3.0,3)
call PLOTD (0.0,3.0,2)
call PLOTD (0.0,4.0,3)
call PLOTD (7.0,4.0,2)

C
      return
      end

C =====
C   Subroutine PLTCRV -- calculates curves based on input arrays
C =====
C
c
      Subroutine PLTCRV (STP,APTS,BPTS,NUMPTS,CRVTYP,CRVNUM,
      *                      TITLE,STITLE,NC,AFIRST,ADELTA,BFIRST,BDELTA)
      real ATEMP(102),BTEMP(102),APTS(1002),BPTS(1002),CRVNUM(10),
      *      STITLE,CRVTYP,AFIRST,ADELTA,BFIRST,BDELTA
      integer STP,FRST,DELT,INTRVL,NC,NUMPTS,EXPAND,SYMBL
      character*30 TITLE
      common/box/ EXPAND,SYMBL
      common/factr/ FACT
      common/symb/ SYMBL

      call FACTOR (FACT)
      call ASPECT (1.2)
      call STAXIS (.13,.20,.15,0.1,2)
      INTRVL = 0
      FRST = STP + 1
      DELT = STP + 2
      call SCALE (APTS,7.0,STP,1)
      ATEMP(101) = APTS(FRST)
      ATEMP(102) = APTS(DELT)
      AFIRST = APTS(FRST)
      ADELTA = APTS(DELT)
      write (*,120) ATEMP(101),ATEMP(102)
120      format (///,5x,'X Axis Min Value = ',g11.4,5x,'X Axis DELTA = ',
```

```

*      g11.4,/)
call SCALE (BPTS,5.0,STP,1)
BTEMP(101) = BPTS(FRST)
BTEMP(102) = BPTS(DELT)
BFIRST = BPTS(FRST)
BDELT = BPTS(DELT)
write (*,130) BTEMP(101),BTEMP(102)
130  format (5x,'Y Axis Min Value = ',g11.3,5x,'Y Axis DELTA = ',
*           g11.4,////)
write (*,131)
131  format (25x,'*** Calculating Data ***',//++)
call AXIS (.8,.8,'Alpha',-5,-7.0,0.,APTS(FRST),APTS(DELT))
call AXIS (.8,.8,'Beta',4,-5.0,90.,BPTS(FRST),BPTS(DELT))
call SYMBOL (STITLE,6.0,.25,TITLE,0.,NC)

C
C . . . Draw dashed lines at axis increments and surrounding box
call GRID
C
do 140 I = 1,NUMPTS
  do 150 J = 1,100
    ATEMP(J) = APTS(J + INTRVL)
    BTEMP(J) = BPTS(J + INTRVL)
150  continue
call CURVE (ATEMP,BTEMP,100,CRVTYP)
call WHERE (X,Y,FACT)
  call NUMBER (X,Y,0.18,CRVNUM(I),0.,2)
  if ((SYMBL .le. 13) .and. (SYMBL .ge. 0)) then
    call LINE (ATEMP,BTEMP,100,1,-1,SYMBL)
  end if
c      do 161 K = 1,100,99
c        ATEMP(K) = ATEMP(K) / APTS(DELT)
c        BTEMP(K) = BTEMP(K) / BPTS(DELT)
c        call NUMBER (ATEMP(K),BTEMP(K),0.18,CRVNUM(I),0.,2)
c161  continue
INTRVL = INTRVL + 100
140  continue
C
return
end

```

```

C
C **** ASCII MODULE ****
C
C =====
C Subroutine CLR -- clears the screen
C =====
C
C     Subroutine CLR
C     character*1 C1, C2, C3, C4
C     integer IC(4)
C     equivalence (C1,IC(1)),(C2,IC(2)),(C3,IC(3)),(C4,IC(4))
C     data IC/16#1B,16#5B,16#32,16#4A/
C     write(*,1) C1,C2,C3,C4
1    format(1X,4A1)
      return
      end
C
C =====
C Subroutine PSIT -- positions cursor by row and column
C =====
C
C     Subroutine PSIT(ROW,COLUMN)
C     integer IC(4),ROW,COLUMN,L
C     character*1 C1,C2,C5,C8,LC(5)
C     character*5 CBUFF
C     equivalence (C1,IC(1)),(C2,IC(2)),(C5,IC(3)),(C8,IC(4)),
*                  (CBUFF,LC(1))
C     data IC/16#1B,16#5B,16#3B,16#66/
C
C     L=10000+100*ROW+COLUMN
C
C +++ Write Escape Codes to a Character Buffer ***
C     write(CBUFF,2) L
2    format(I5)
C
C +++ Write Escape Codes to Display ***
C     write(*,3) C1,C2,LC(2),LC(3),C5,LC(4),LC(5),C8
3    format(1X,8A1,\)
      return
      end

```

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